

Figure 1

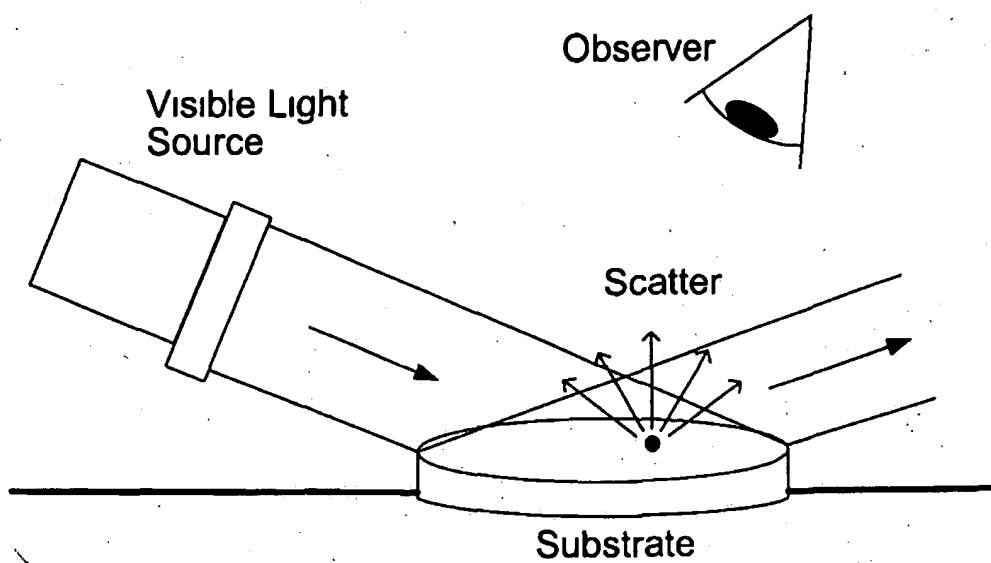


Figure 2

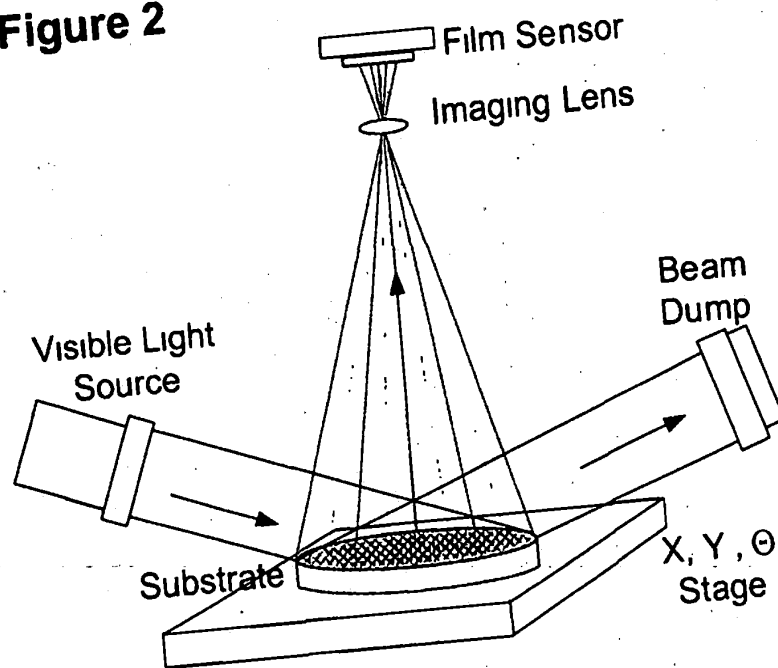


Figure 3

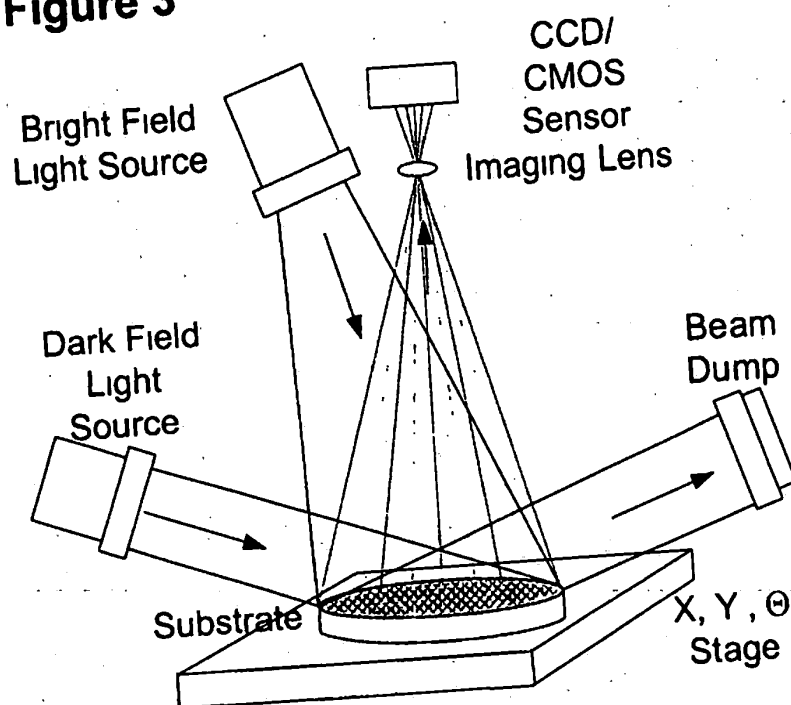


Figure 3A

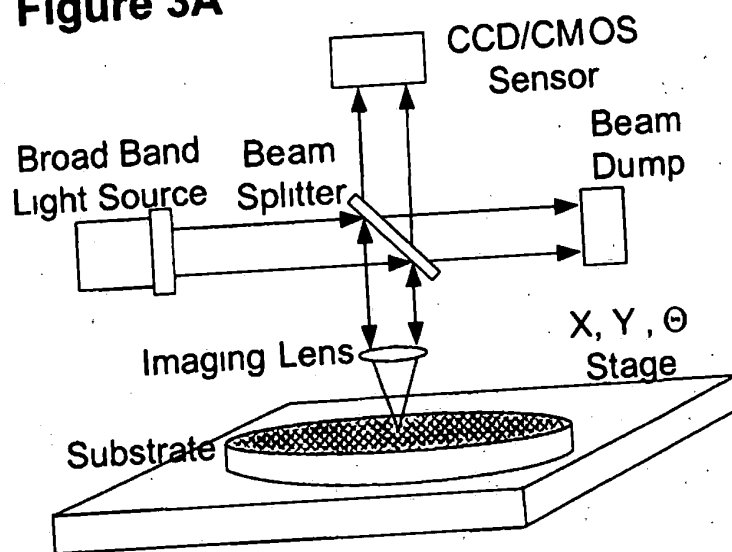


Figure 3B

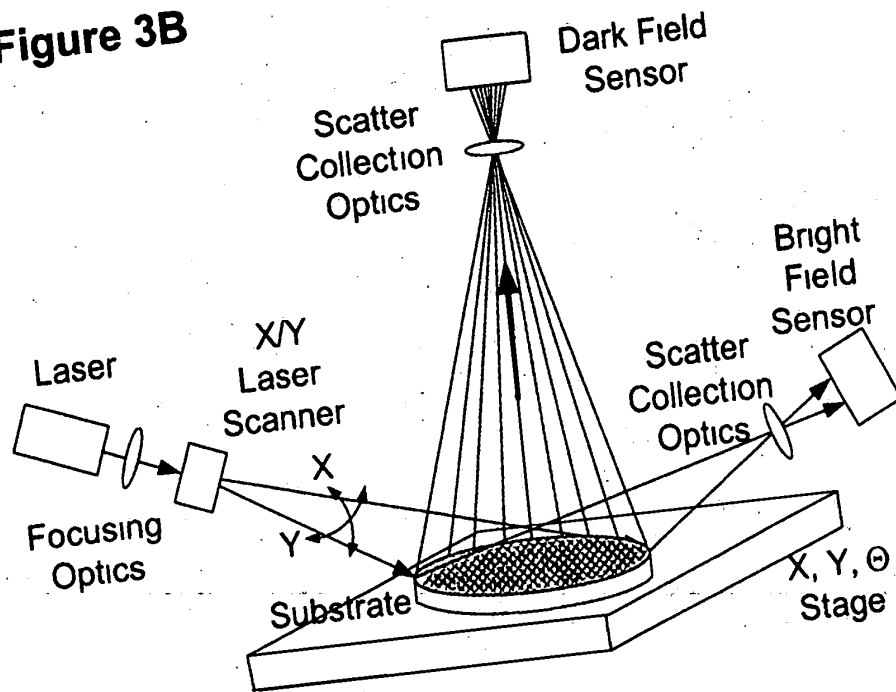


Figure 4A

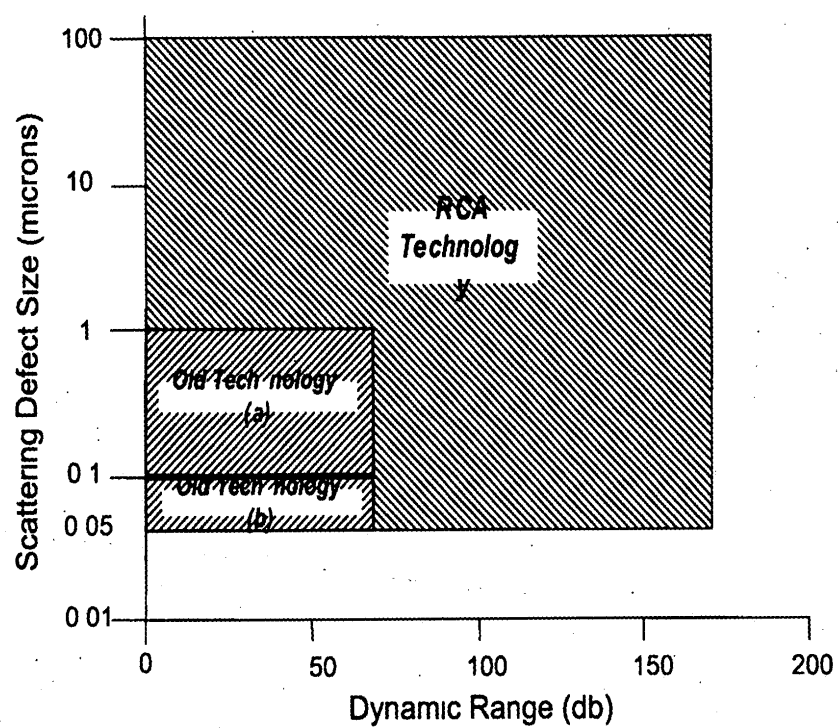


Figure 4B

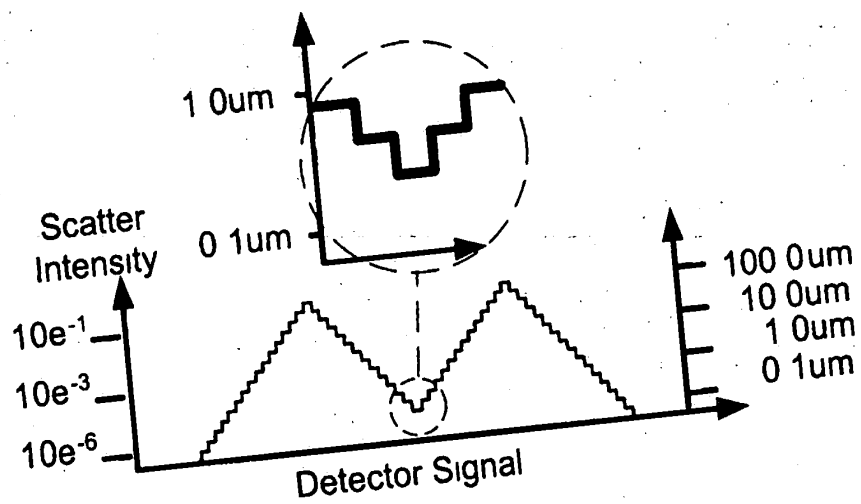
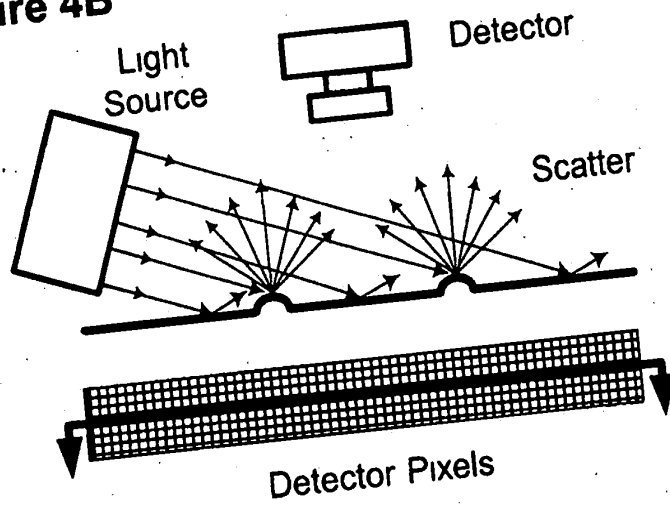


Figure 4C

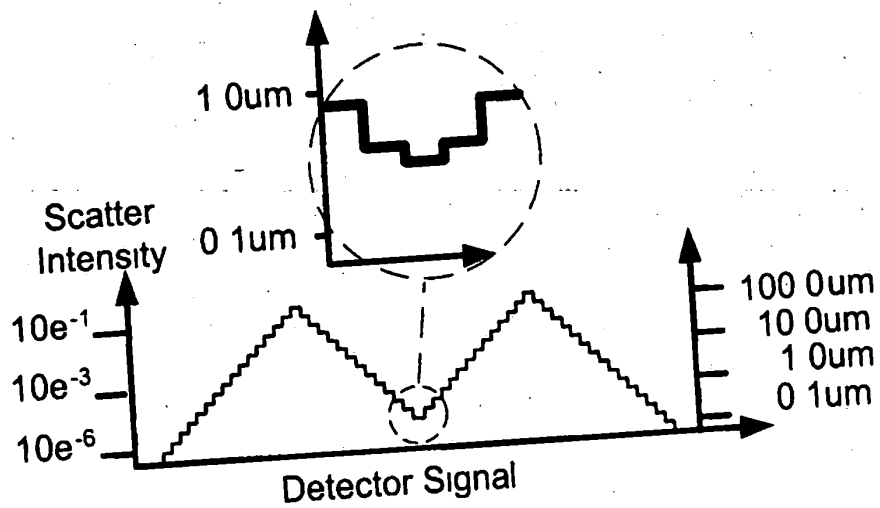
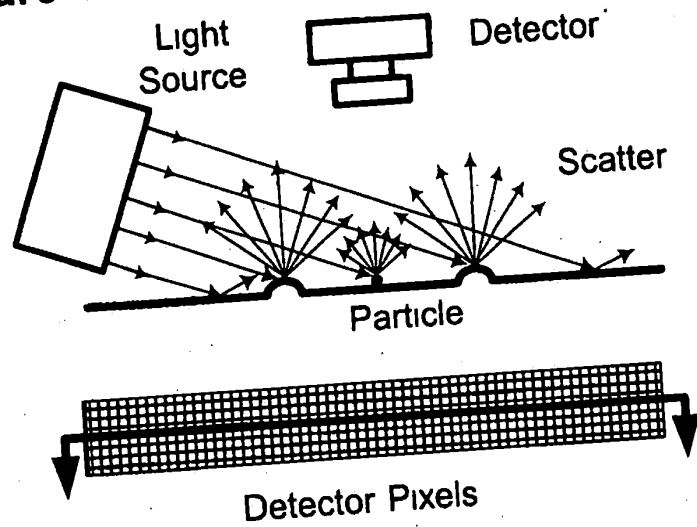


Figure 4D

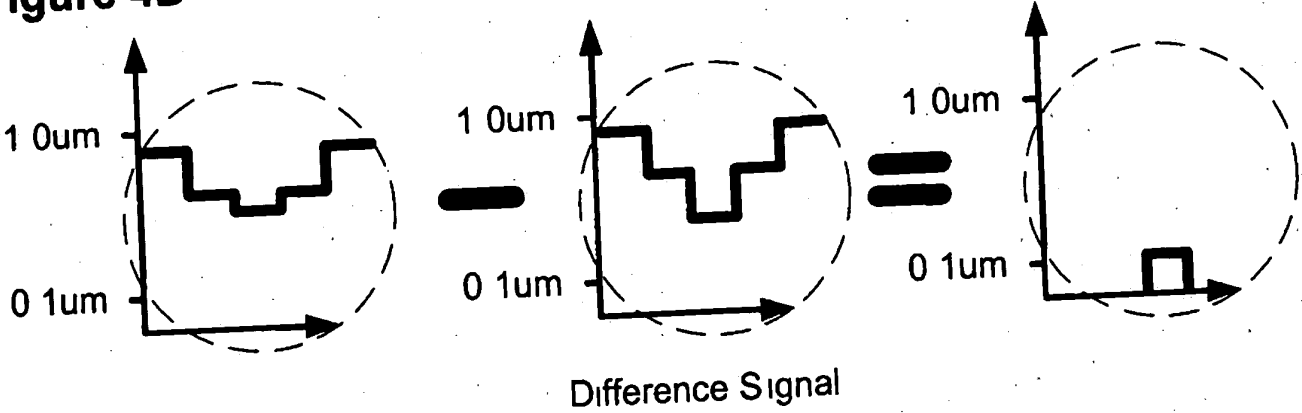


Figure 4E

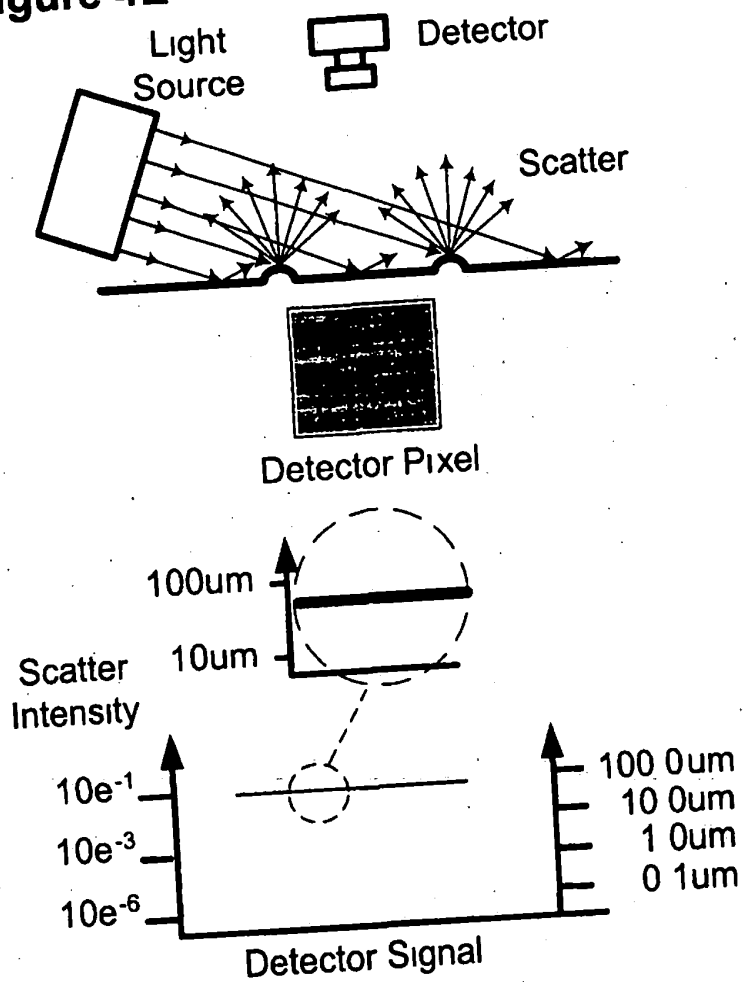


Figure 4F

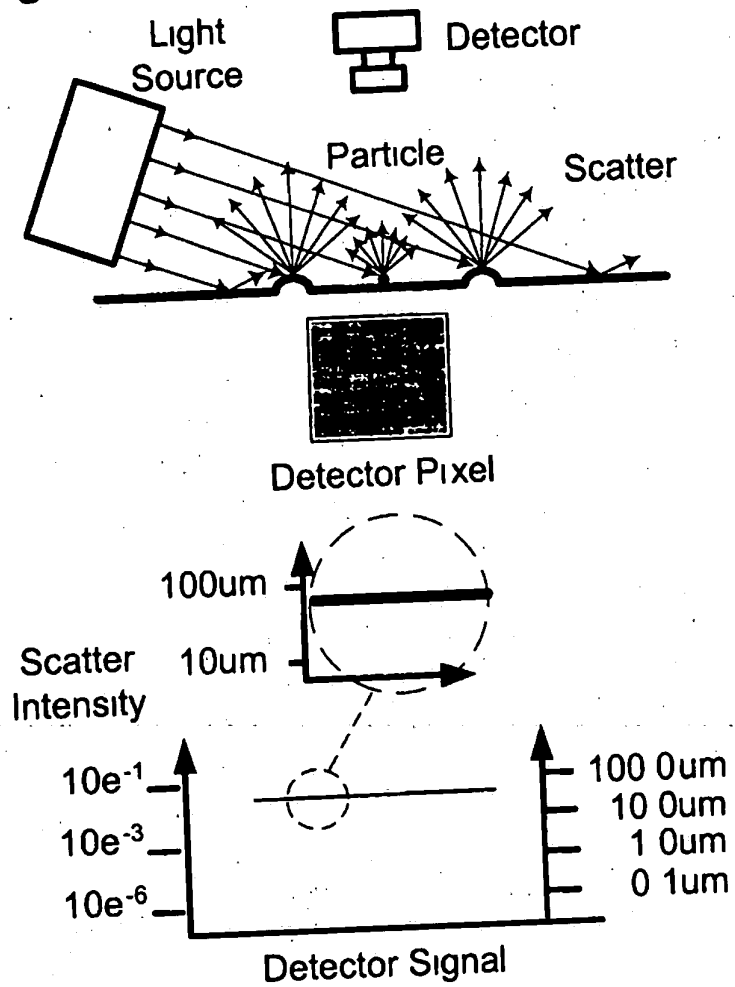
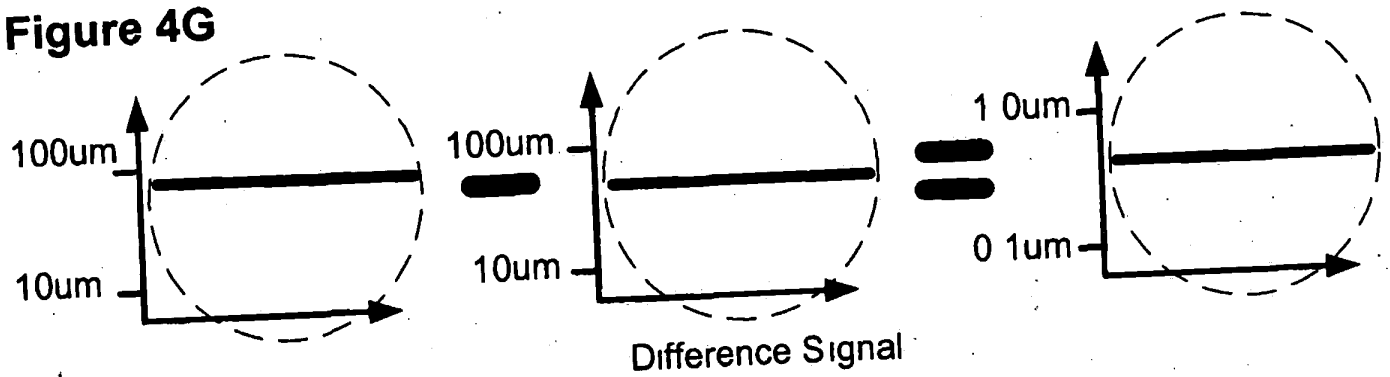


Figure 4G



1.

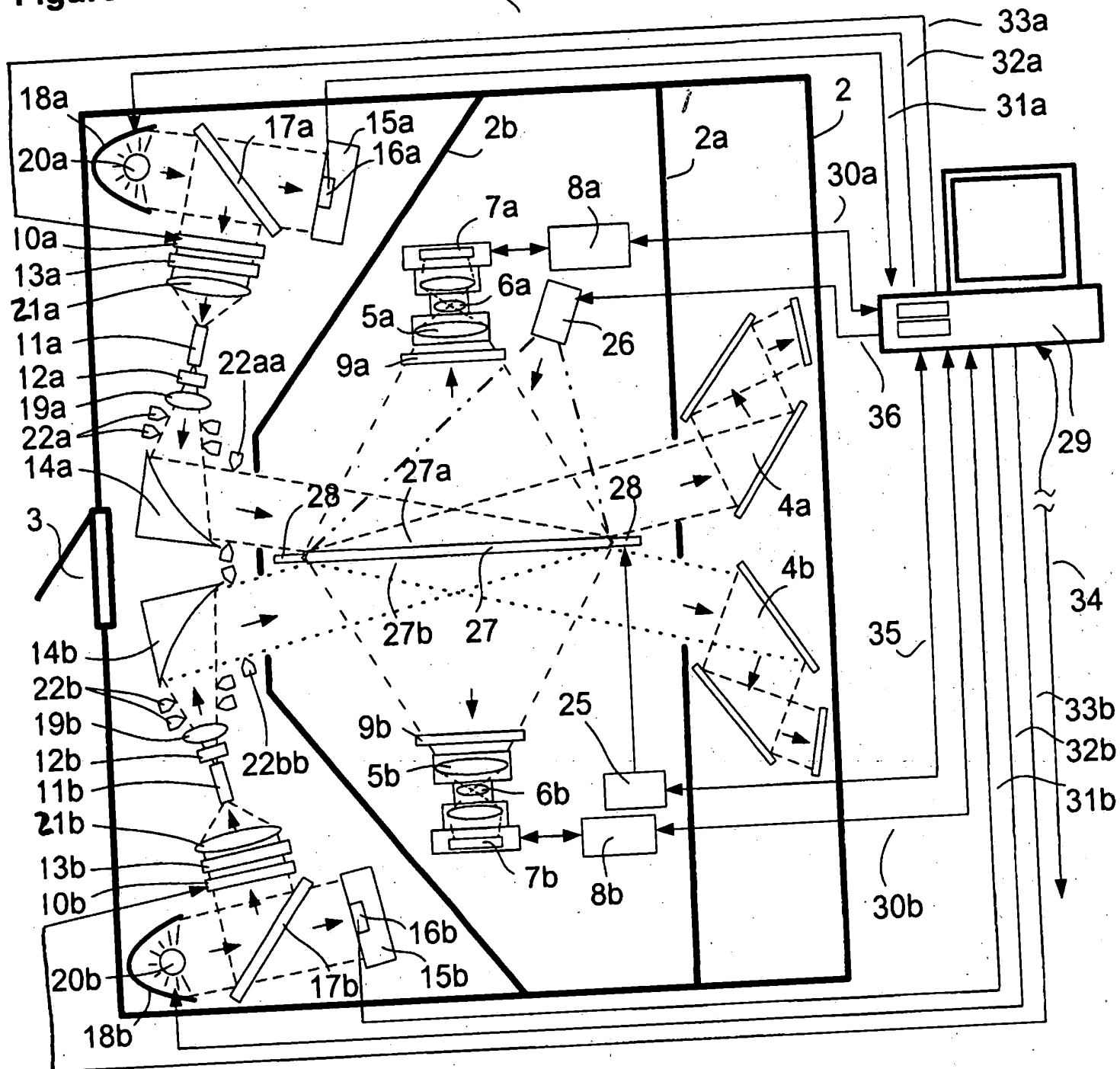


Figure 5A

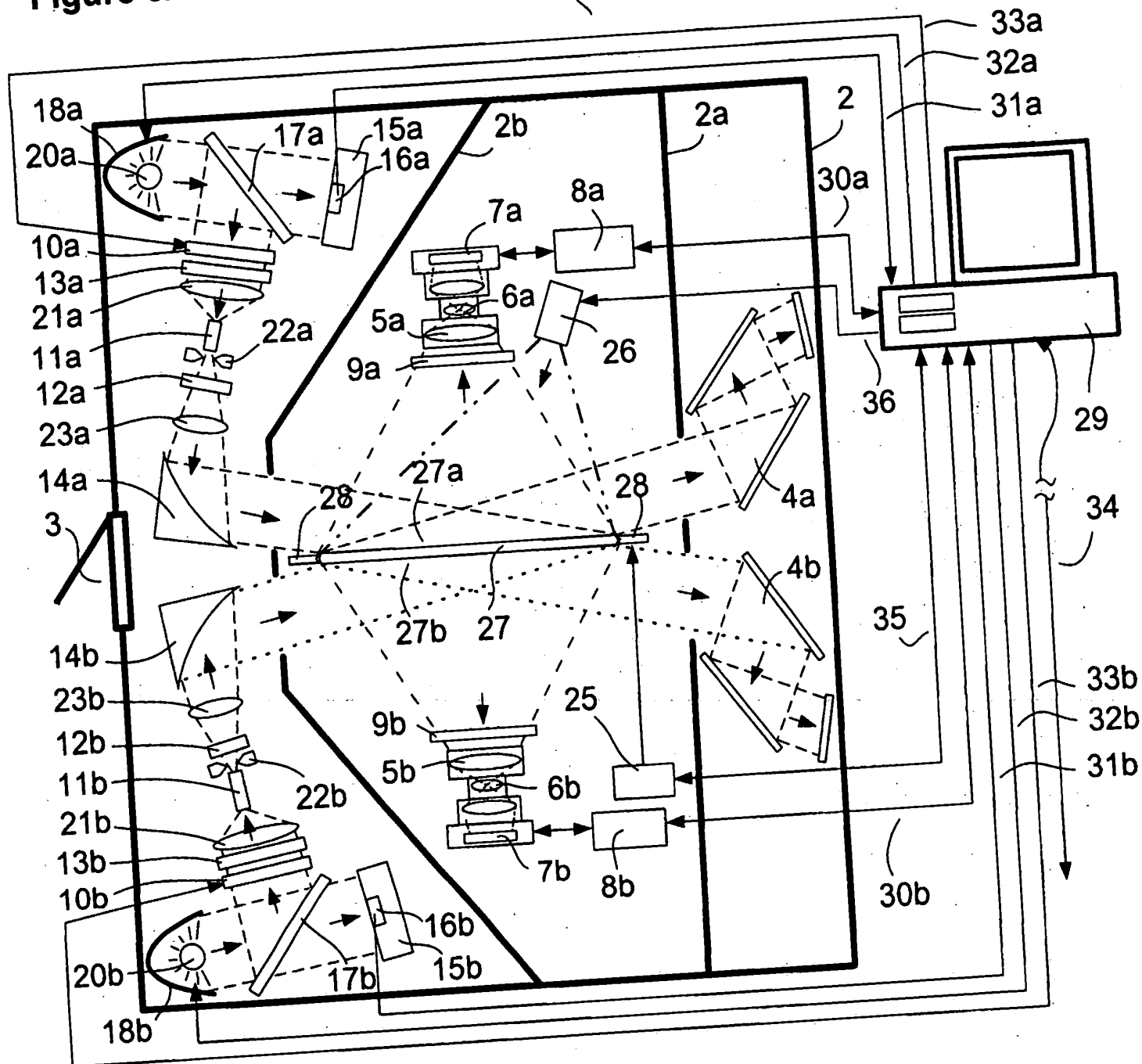


Figure 6

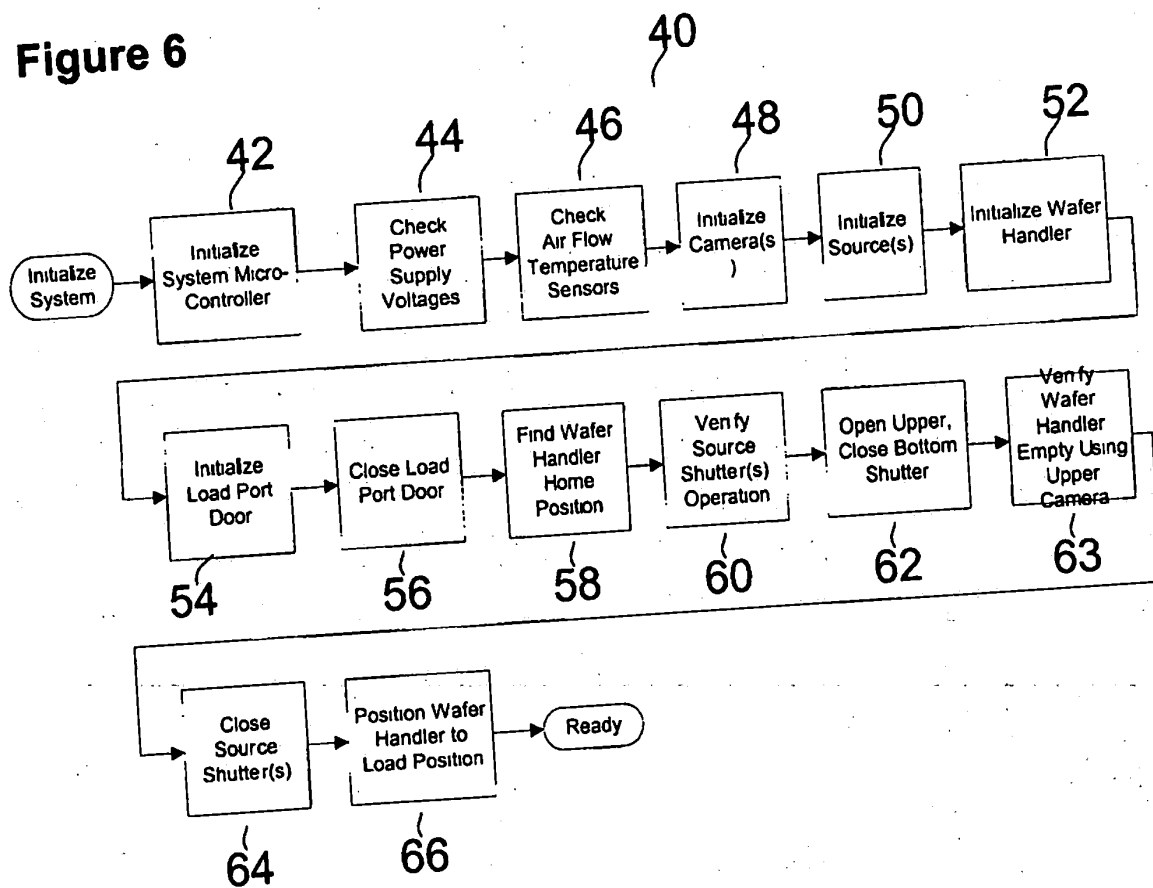


Figure 7

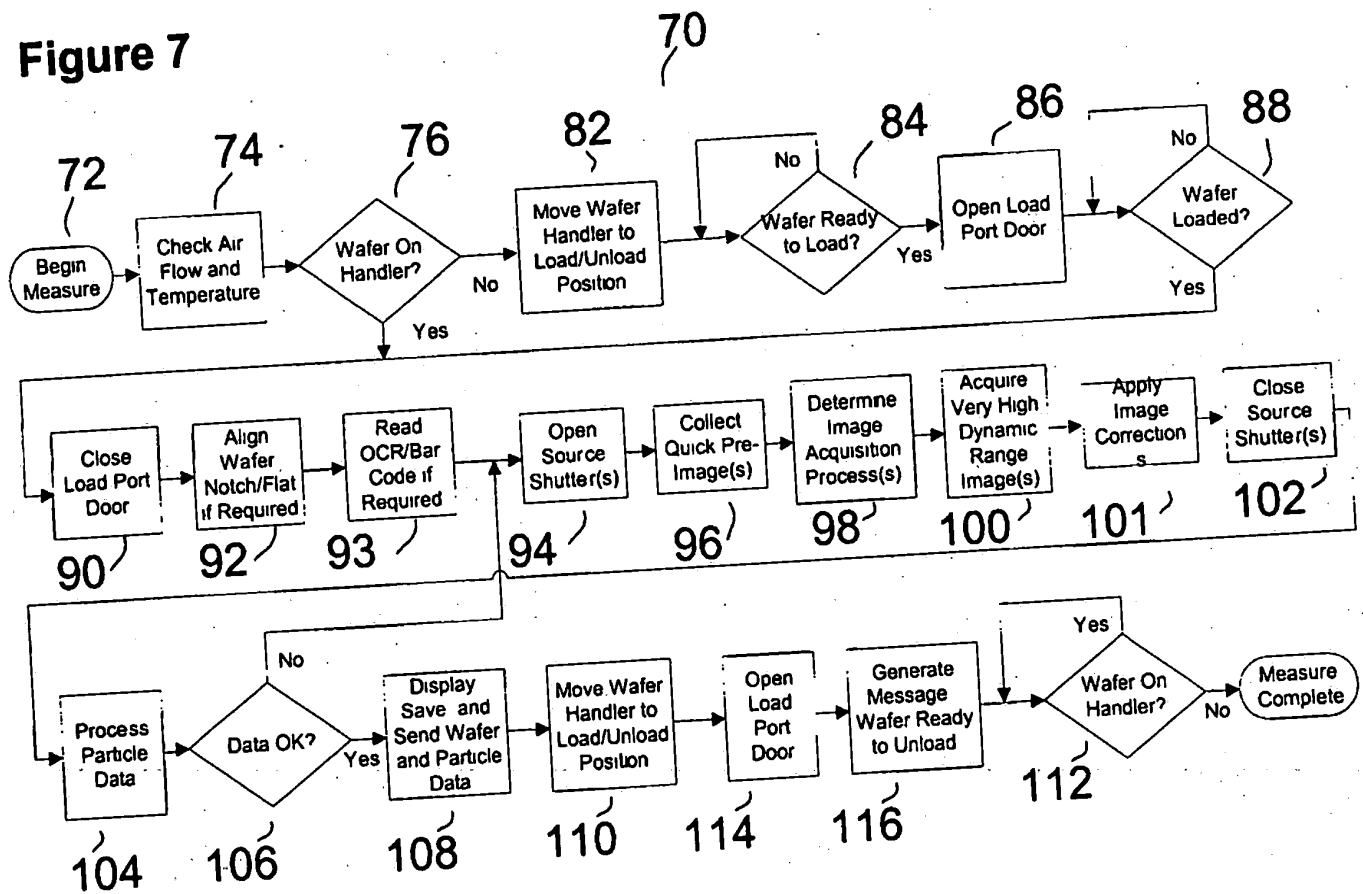


Figure 8

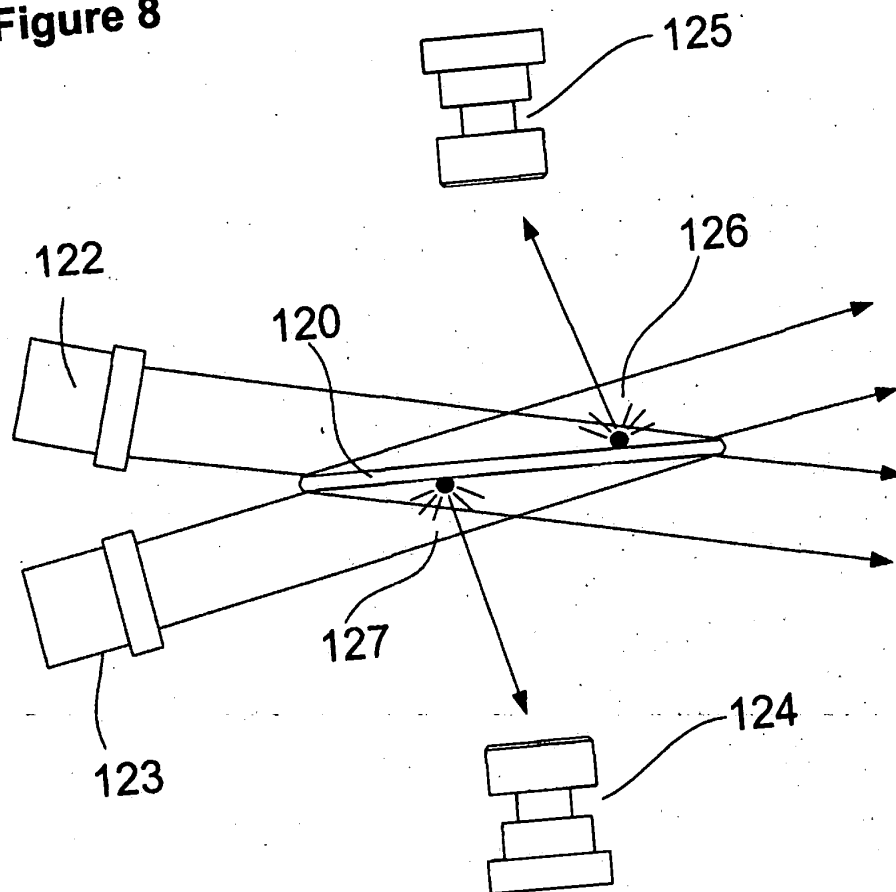


Figure 9

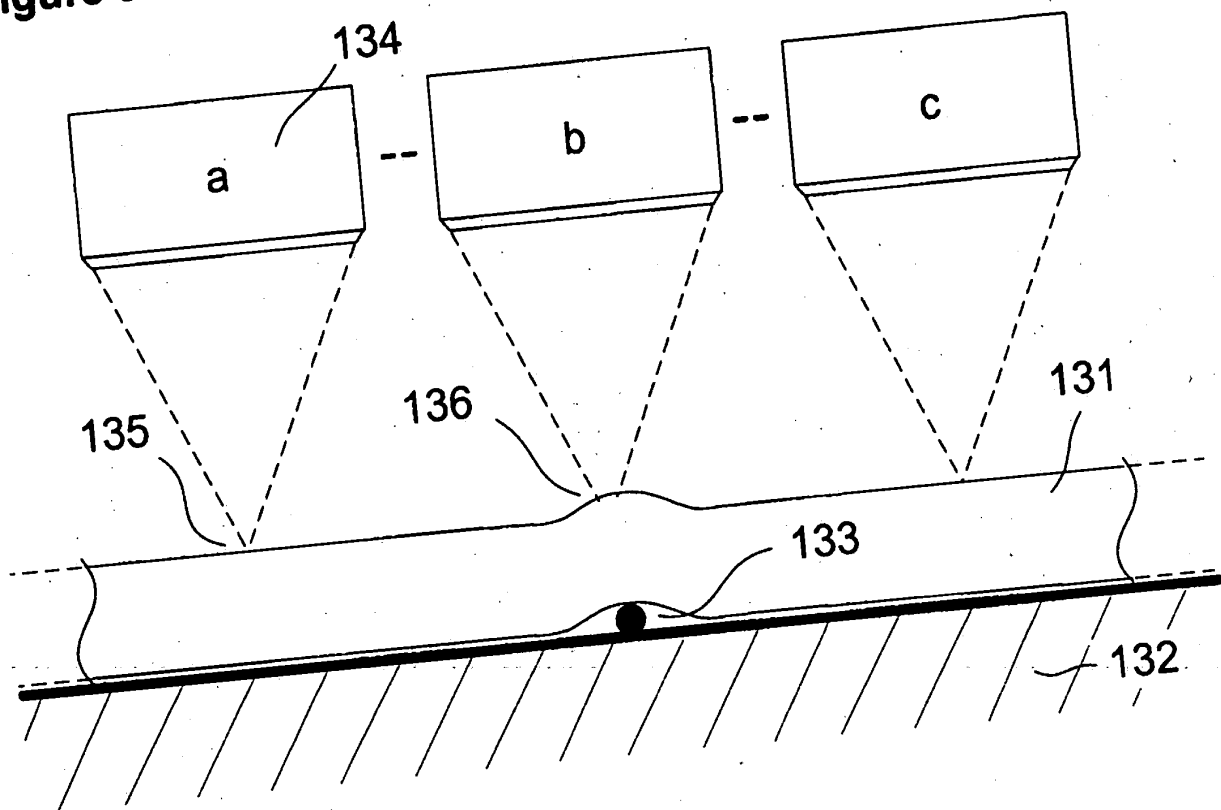


Figure 10

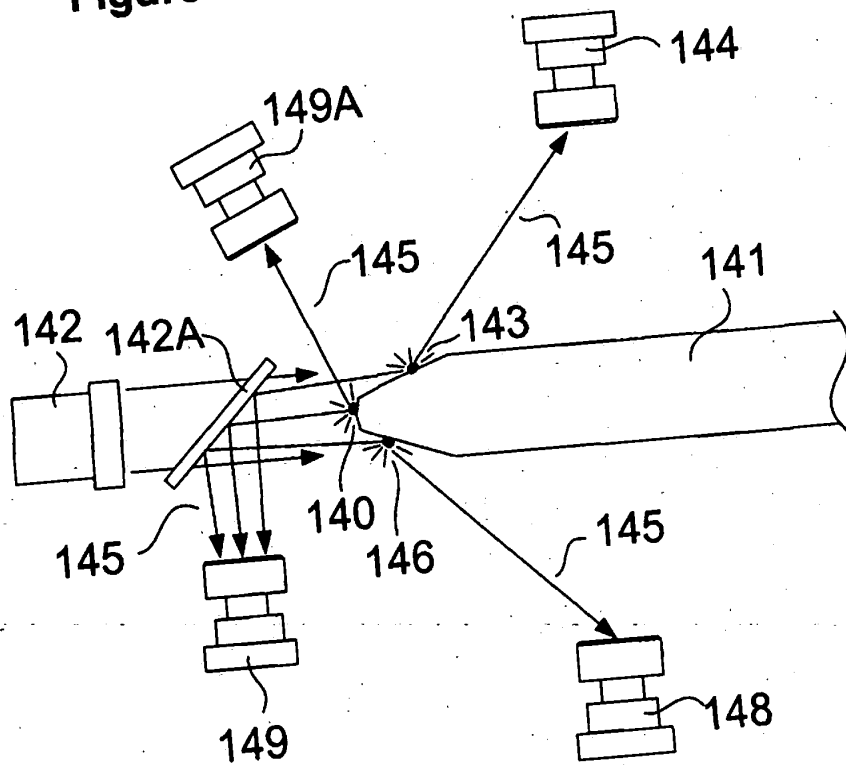


Figure 11

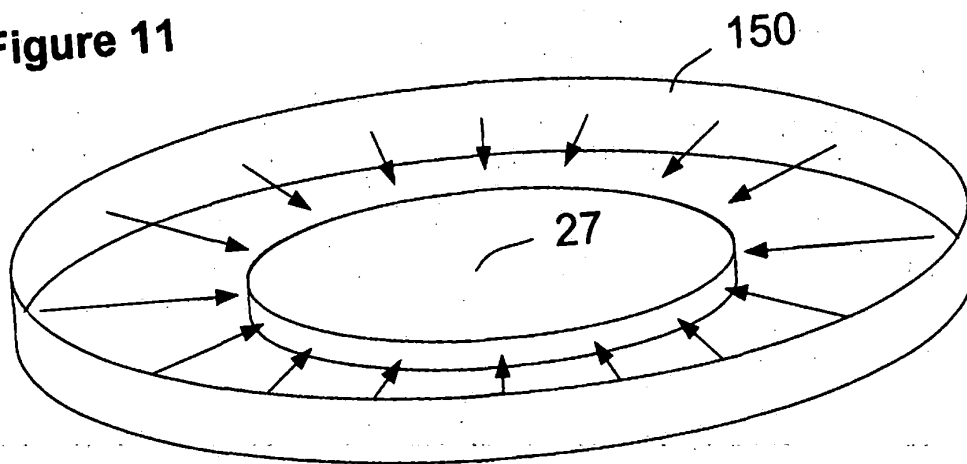


Figure 12

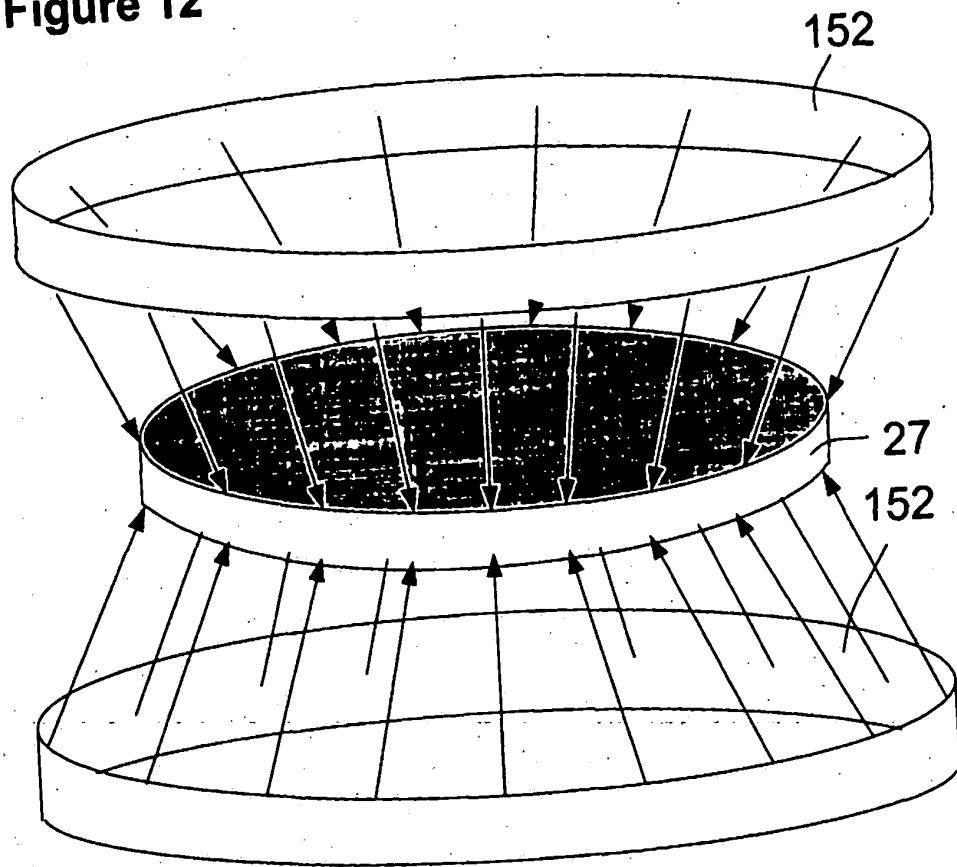


Figure 13A

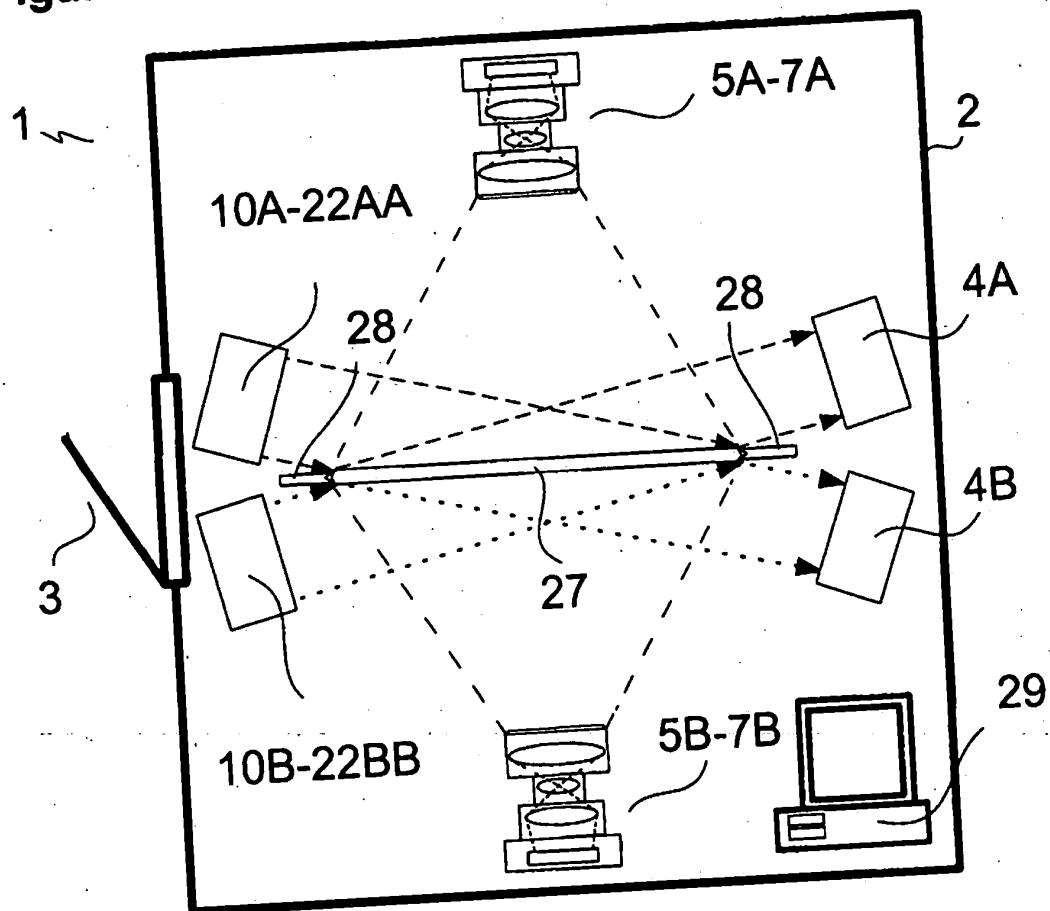


Figure 13B

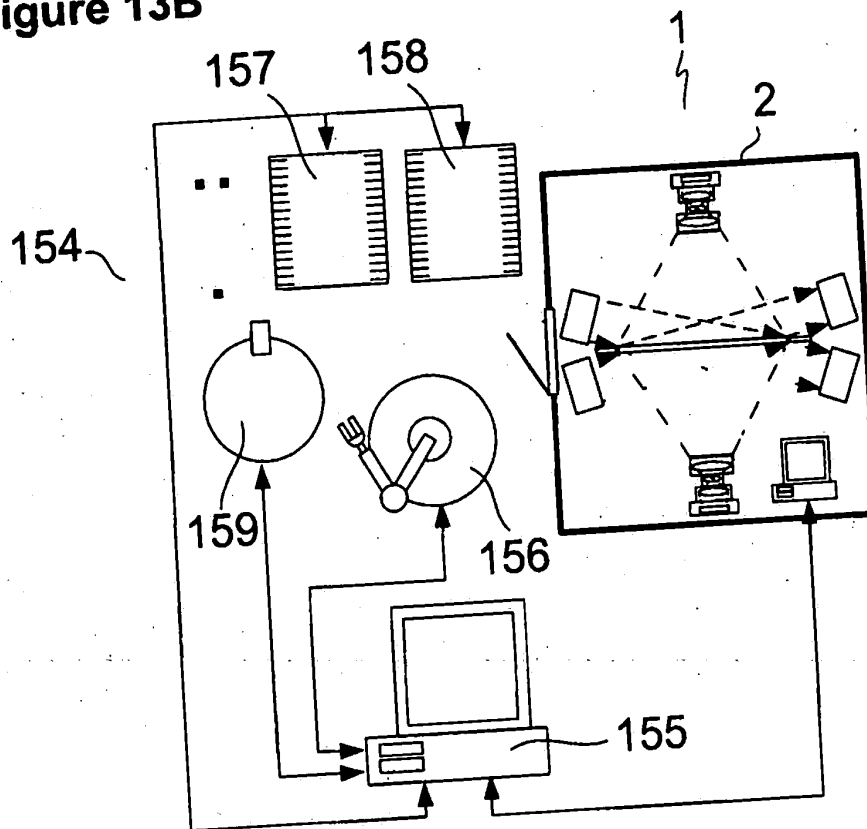


Figure 13C

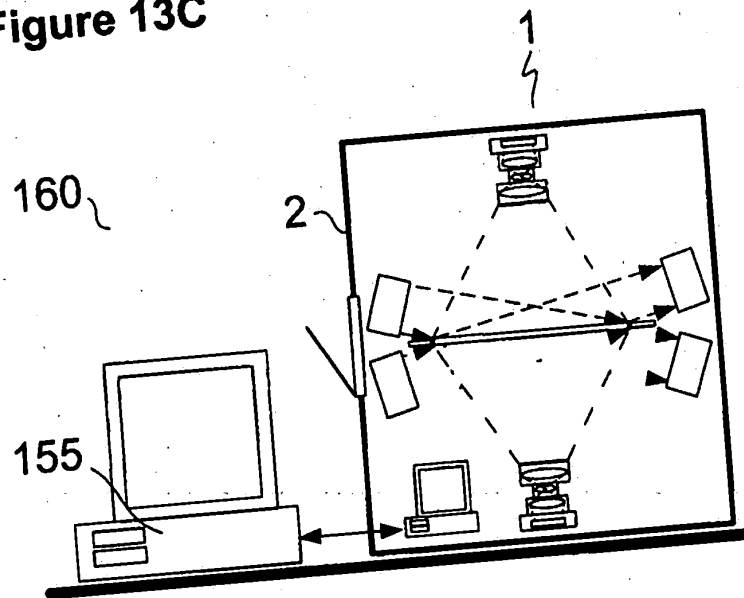


Figure 13D

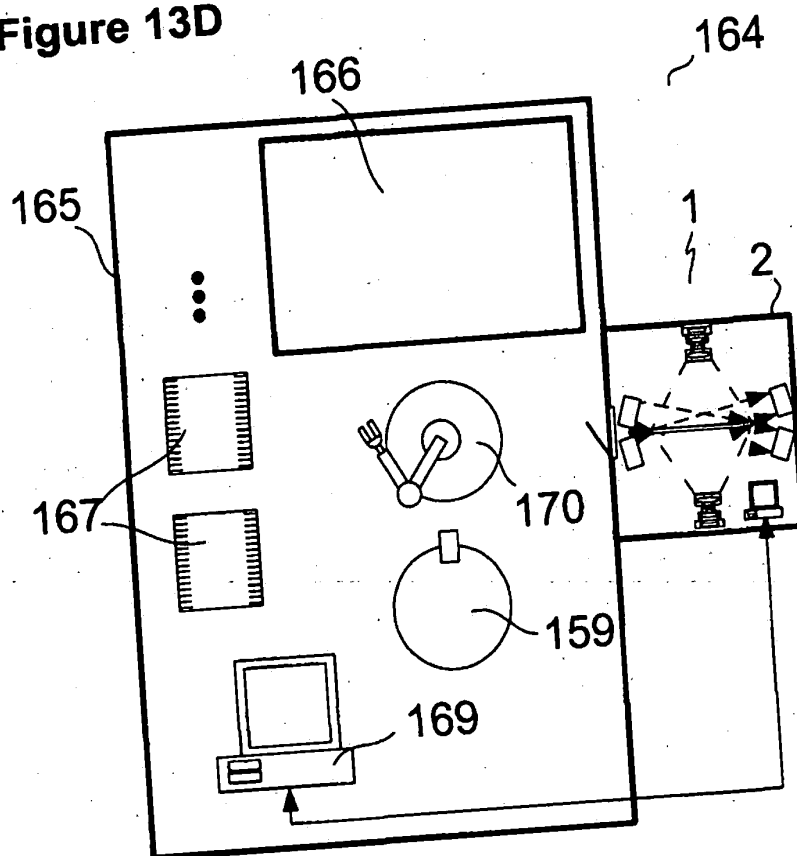


Figure 13E

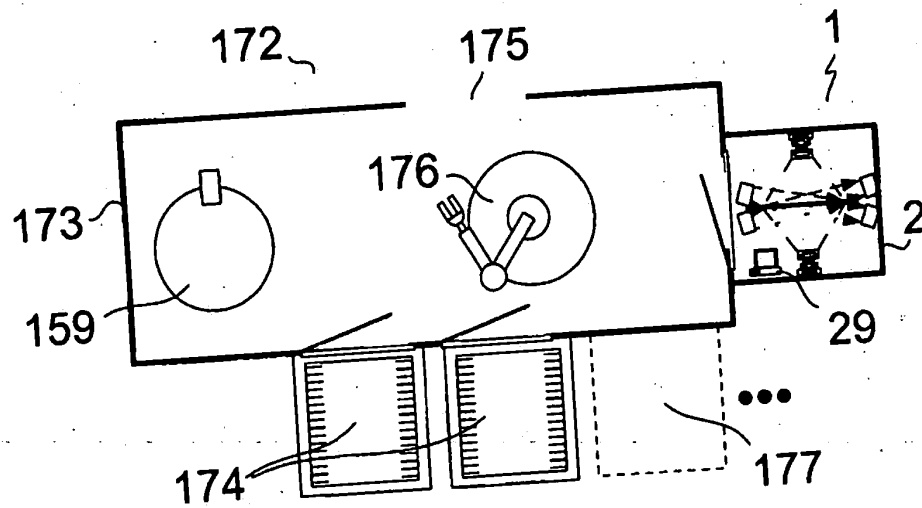


Figure 14

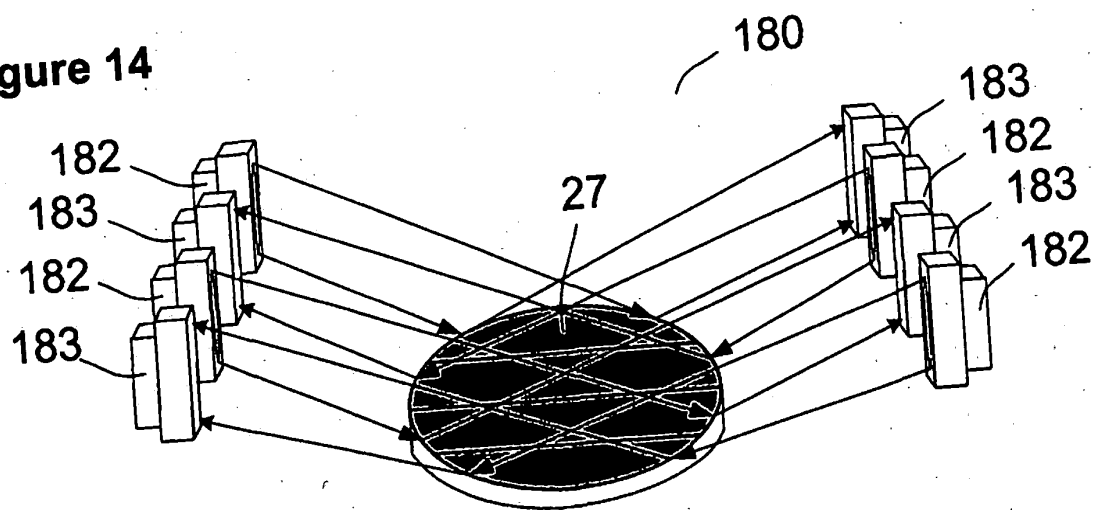


Figure 15

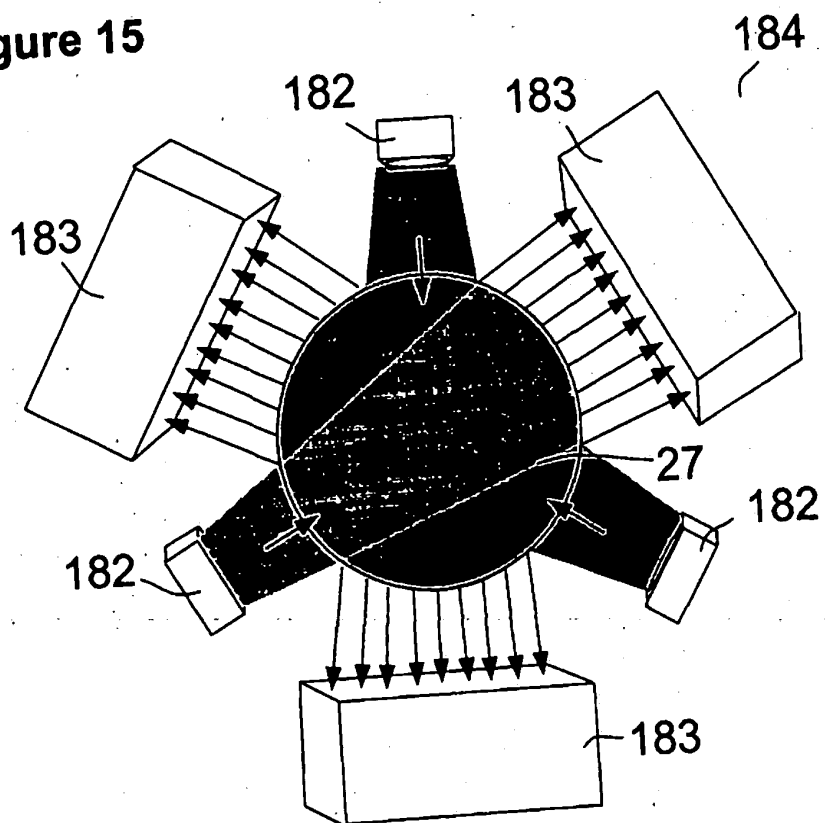


Figure 16

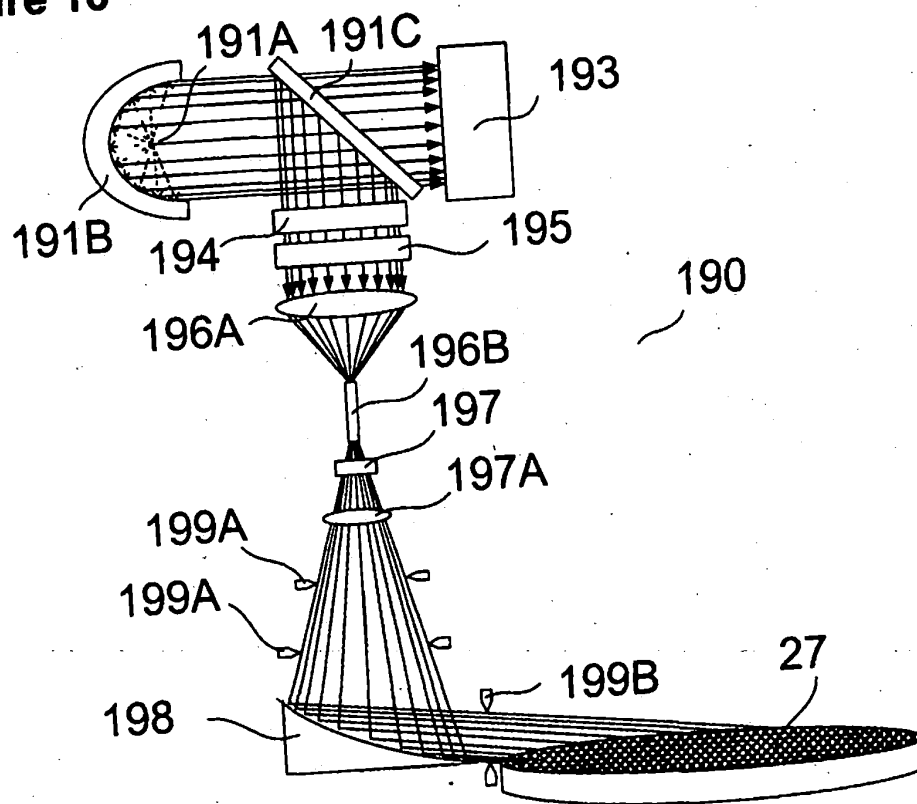


Figure 16A

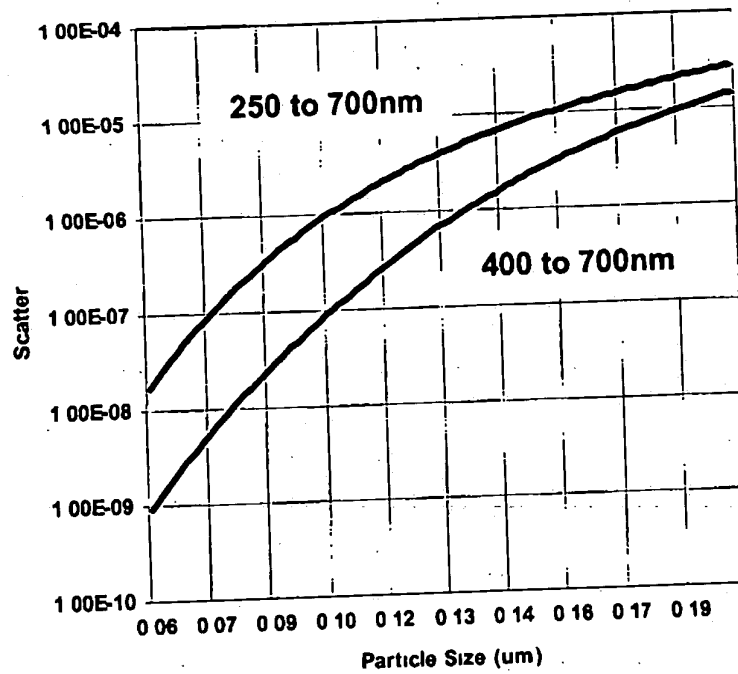


Figure 16B

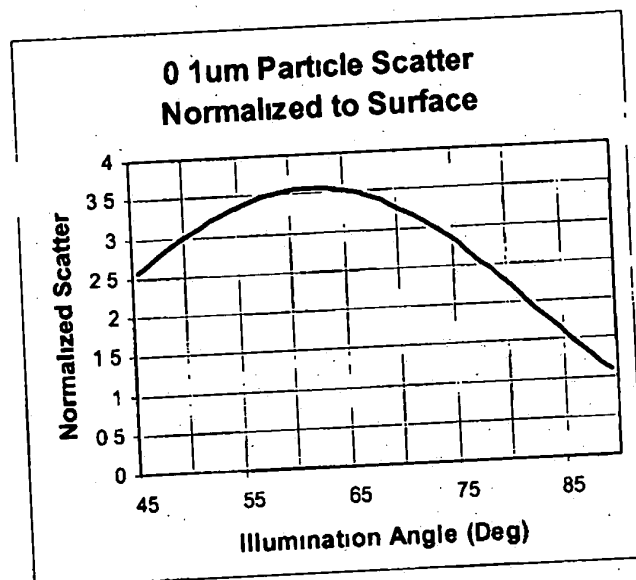
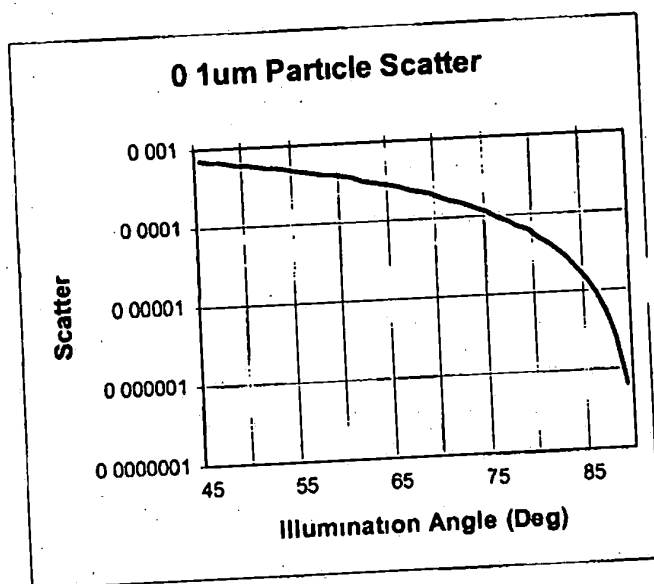


Figure 16C

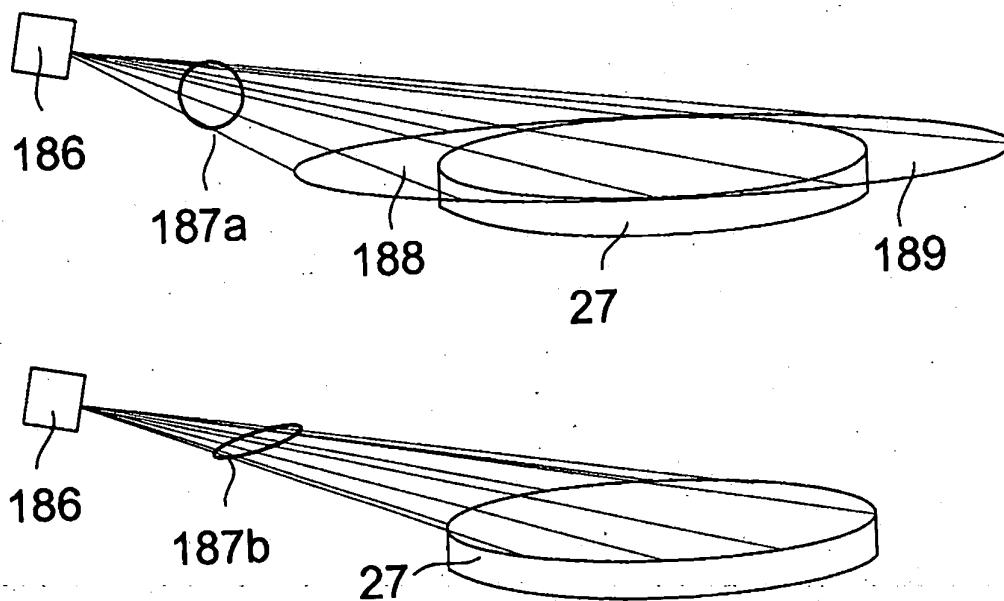
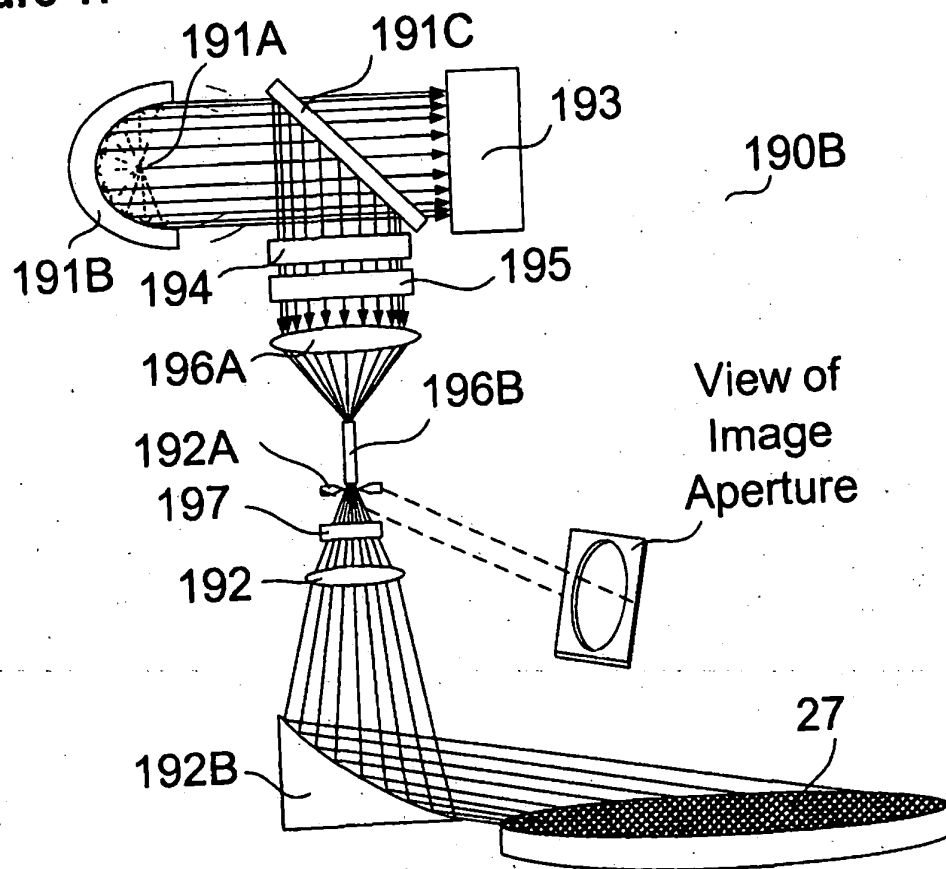


Figure 17



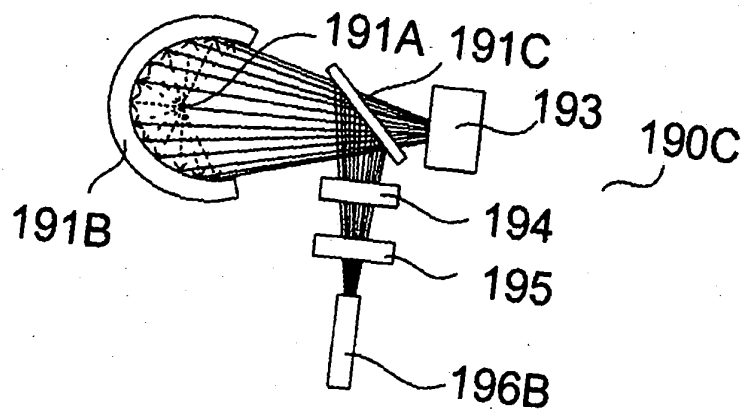


Figure 18

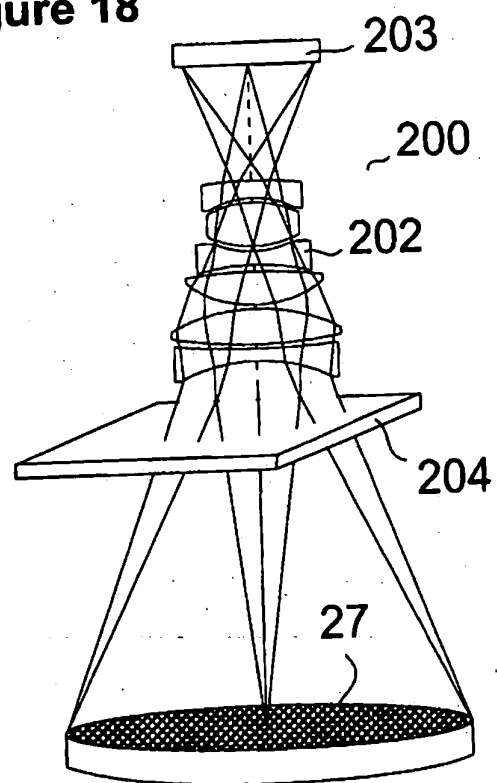


Figure 19

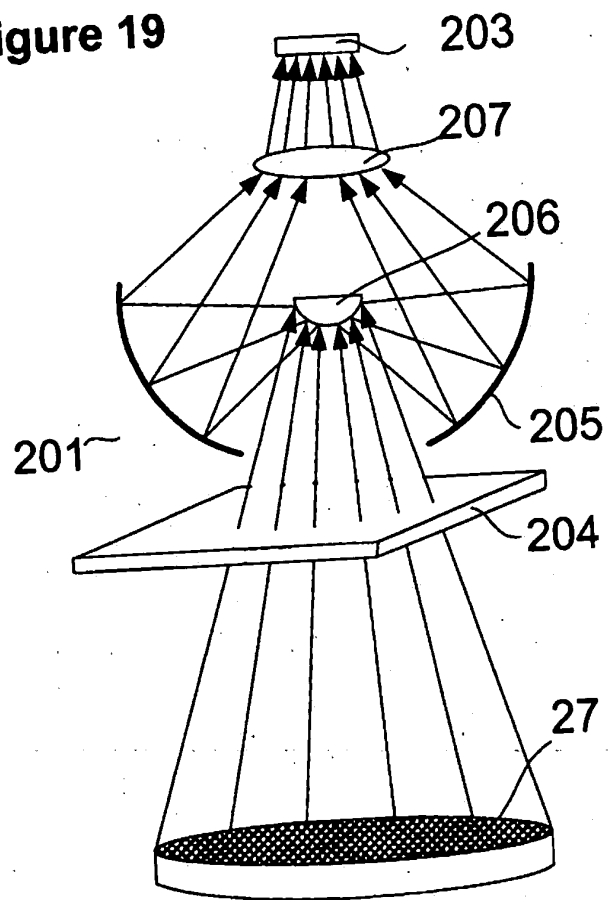


Figure 20

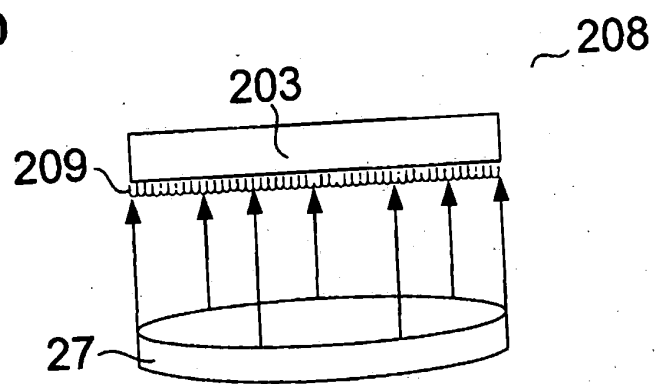


Figure 21A

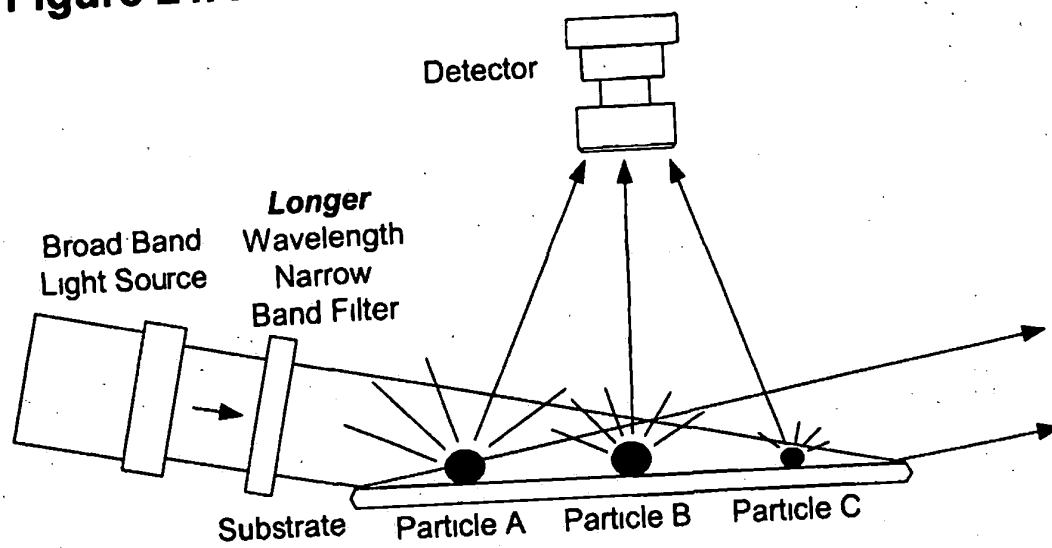


Figure 21B

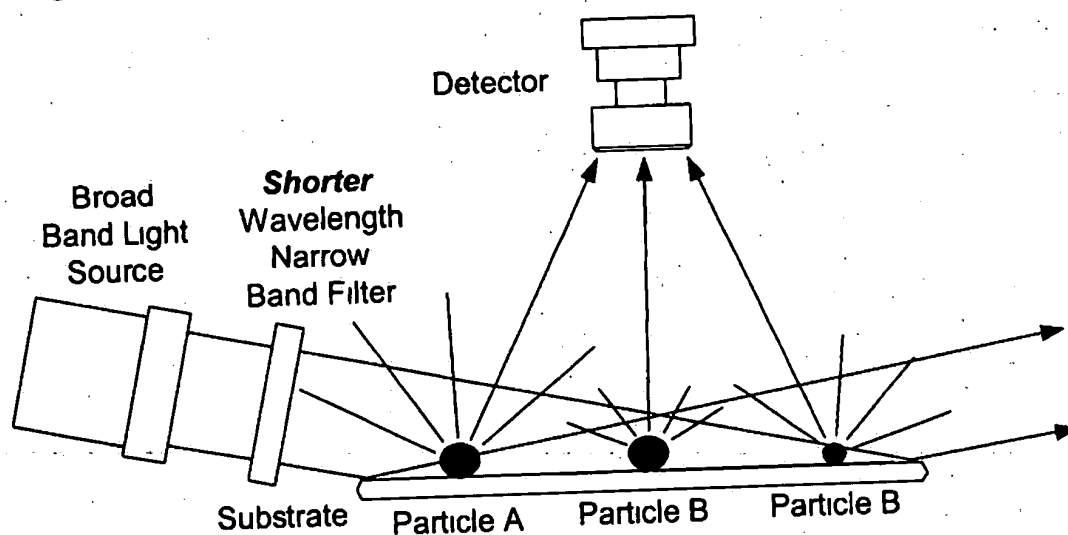


Figure 22

CID - With Anti-Blooming



0.1 sec



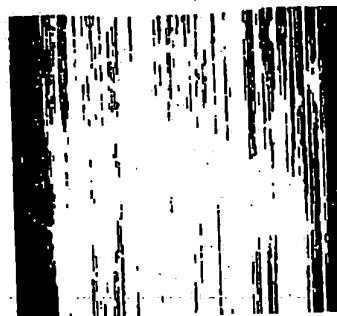
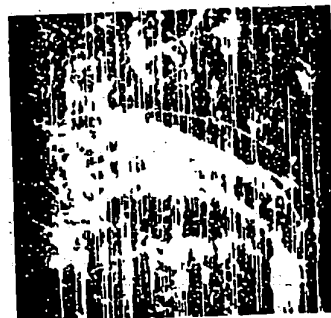
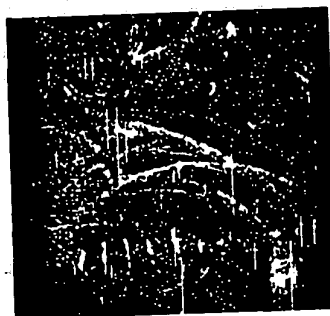
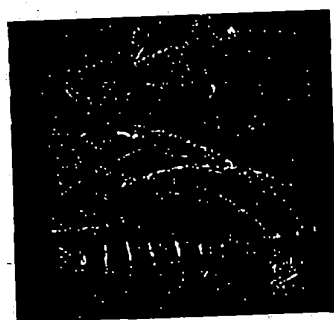
1.0 sec



10.0 sec



60.0 sec



CCD - Without Anti-Blooming

Figure 22A

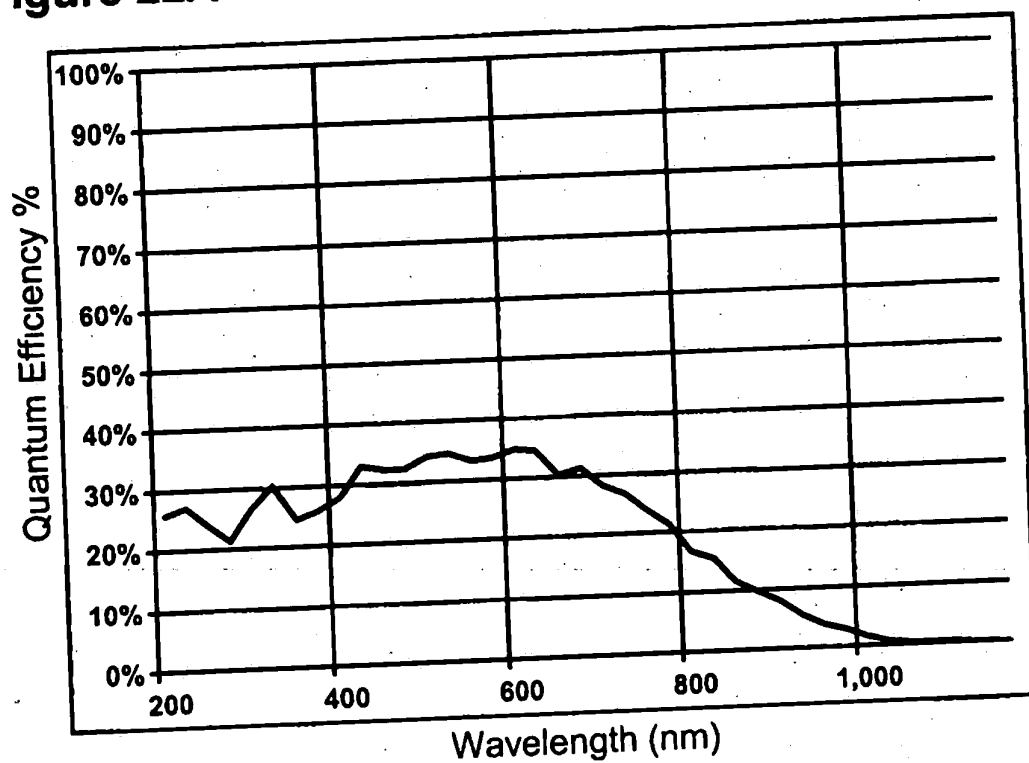


Figure 22B

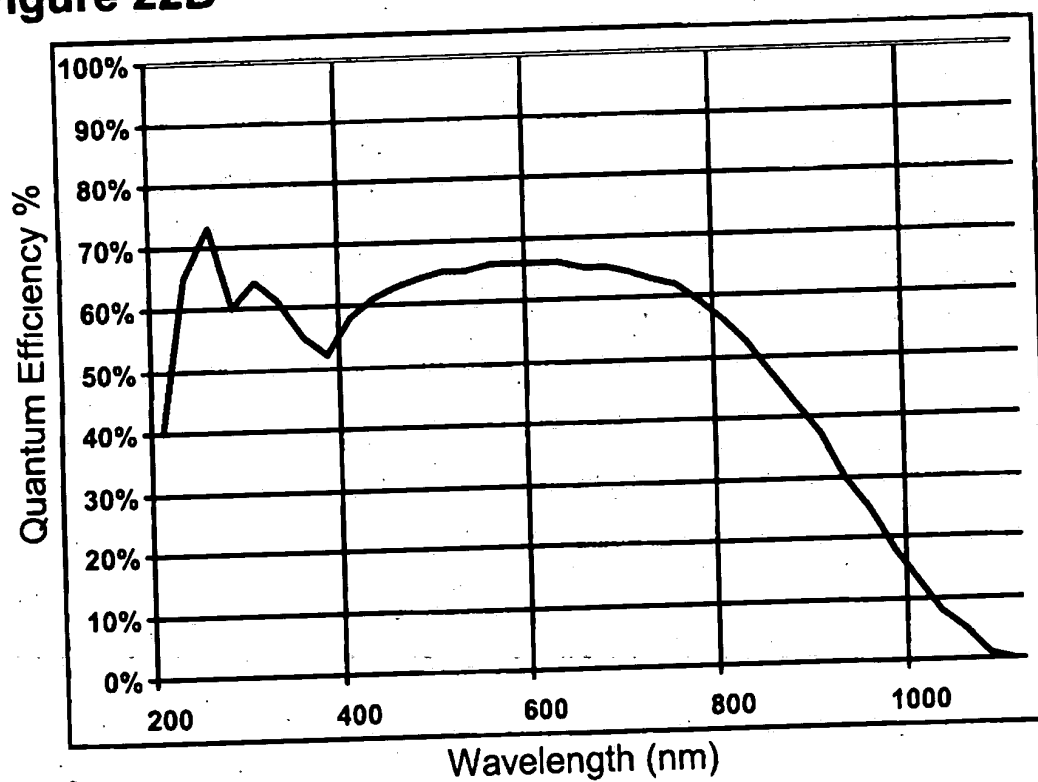


Figure 23B1

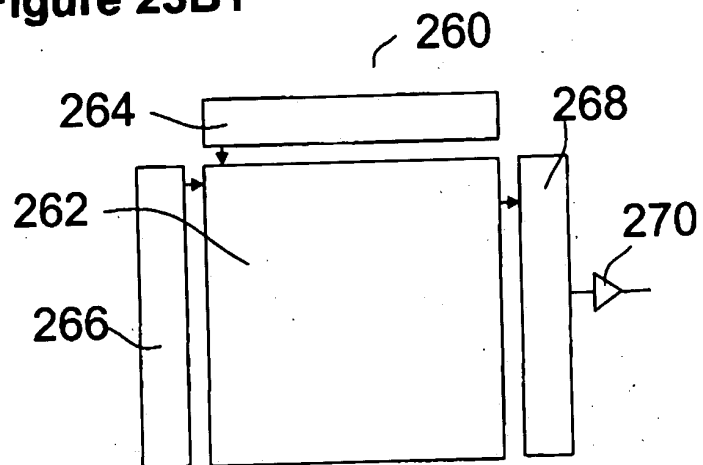


Figure 23B2

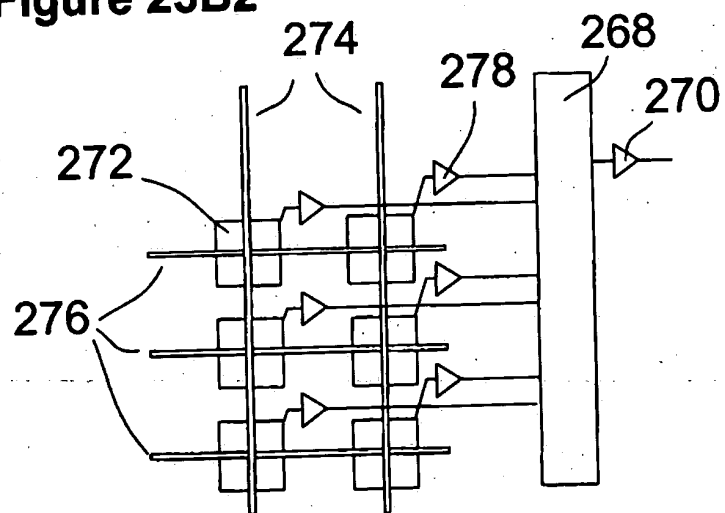


Figure 24

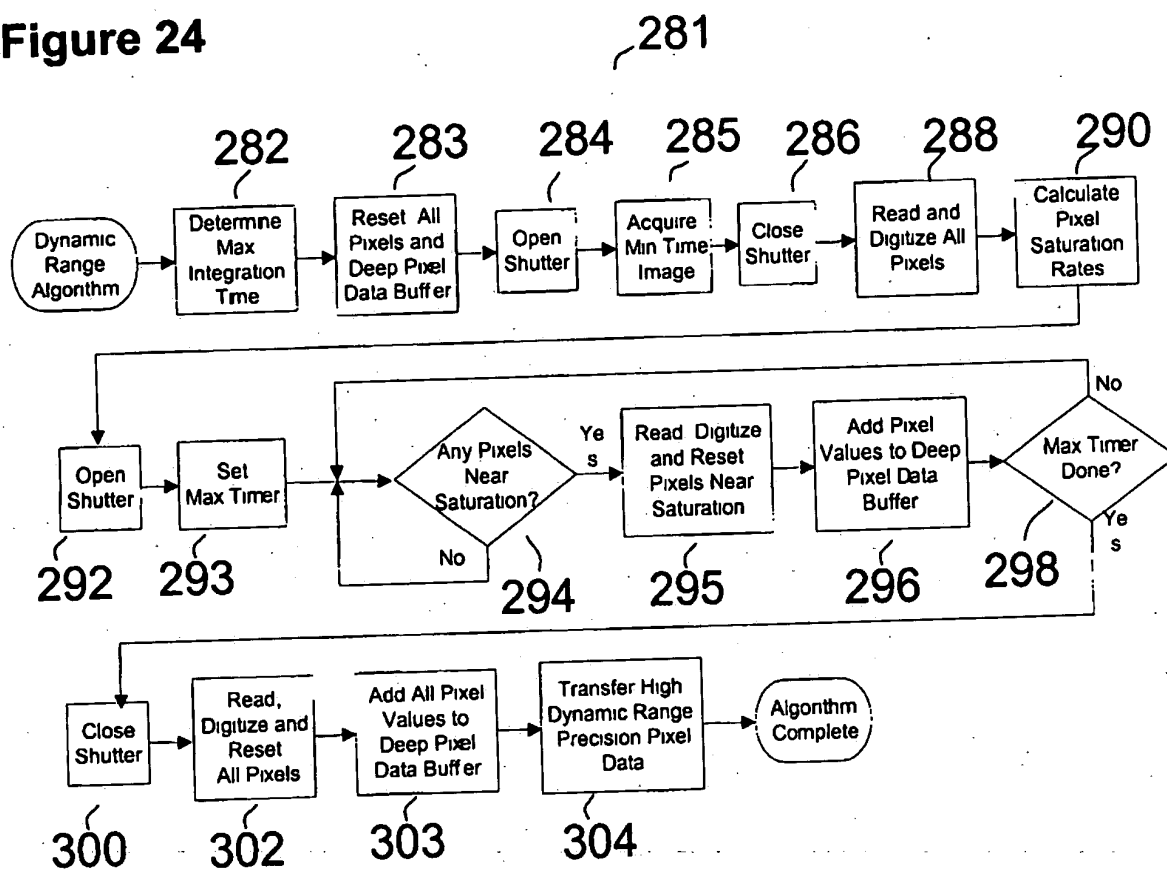


Figure 25

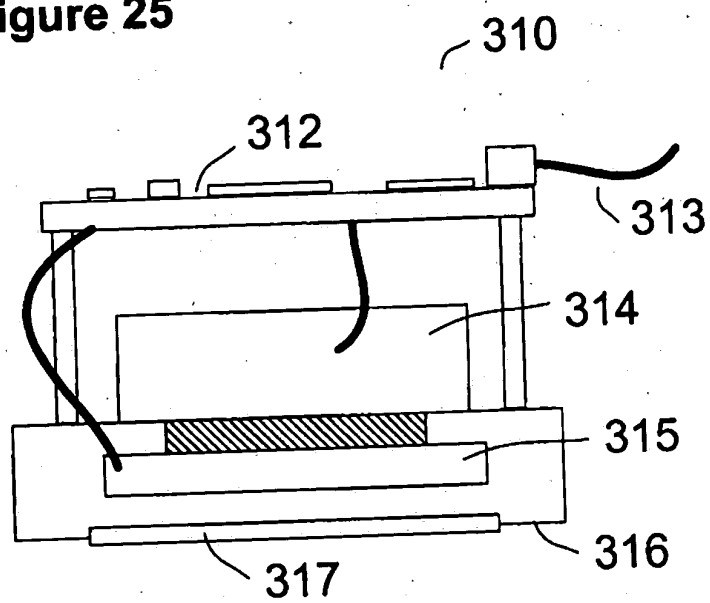


Figure 26A

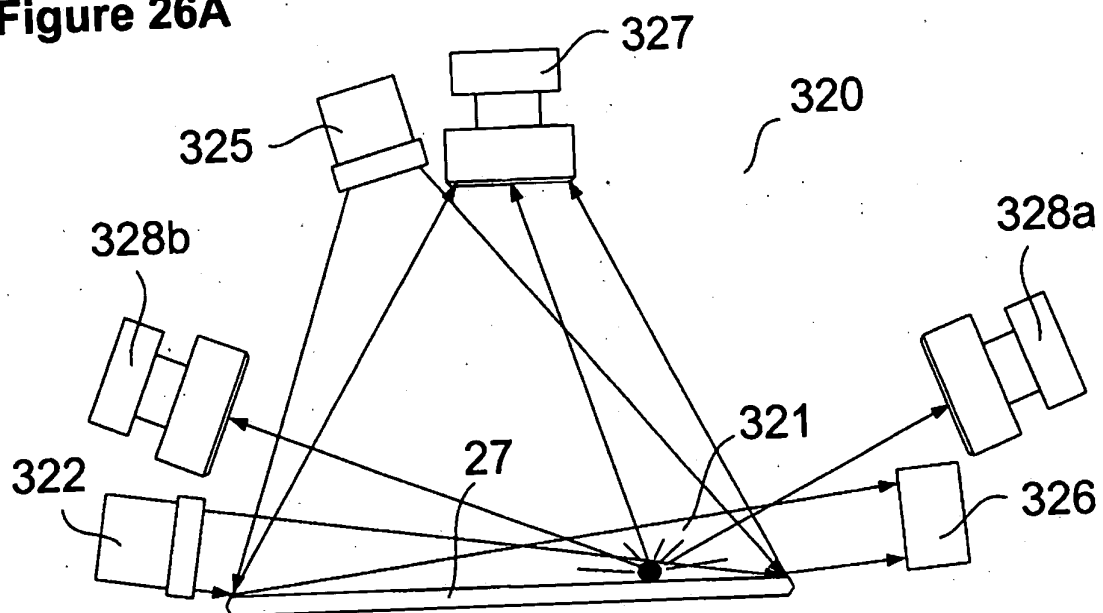


Figure 26B

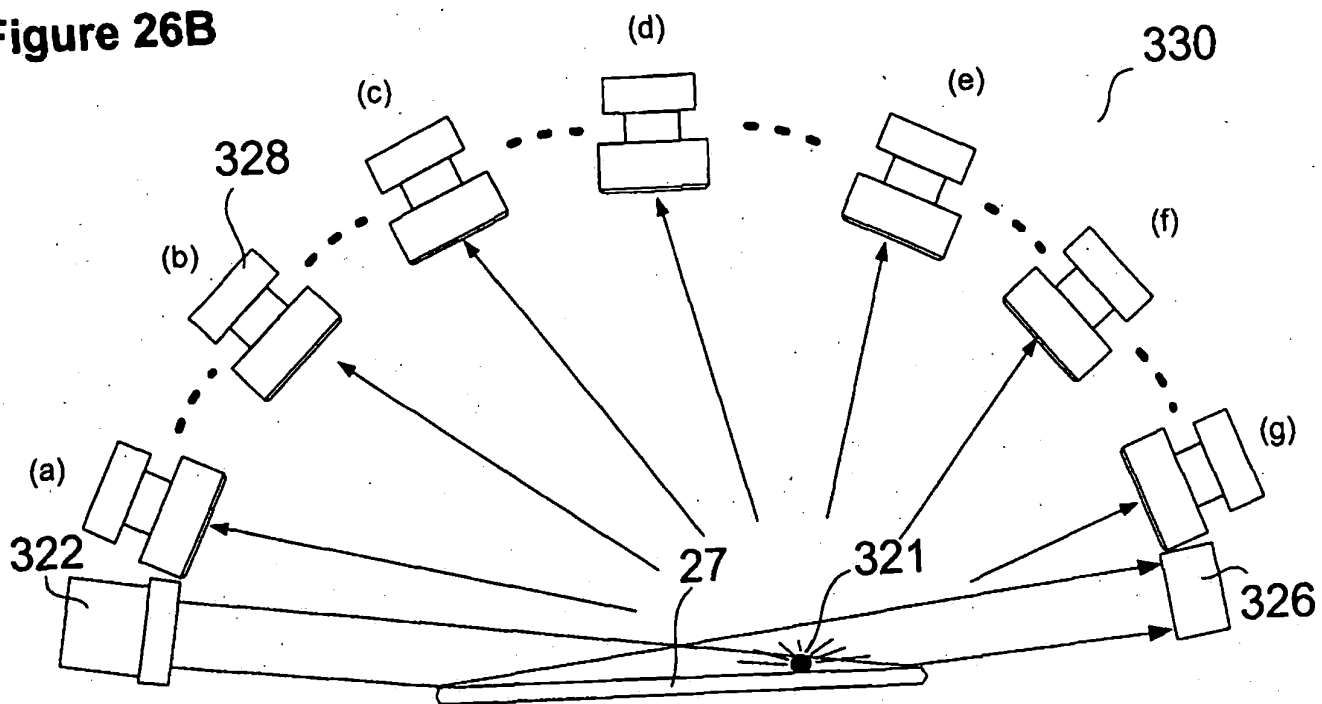


Figure 26C

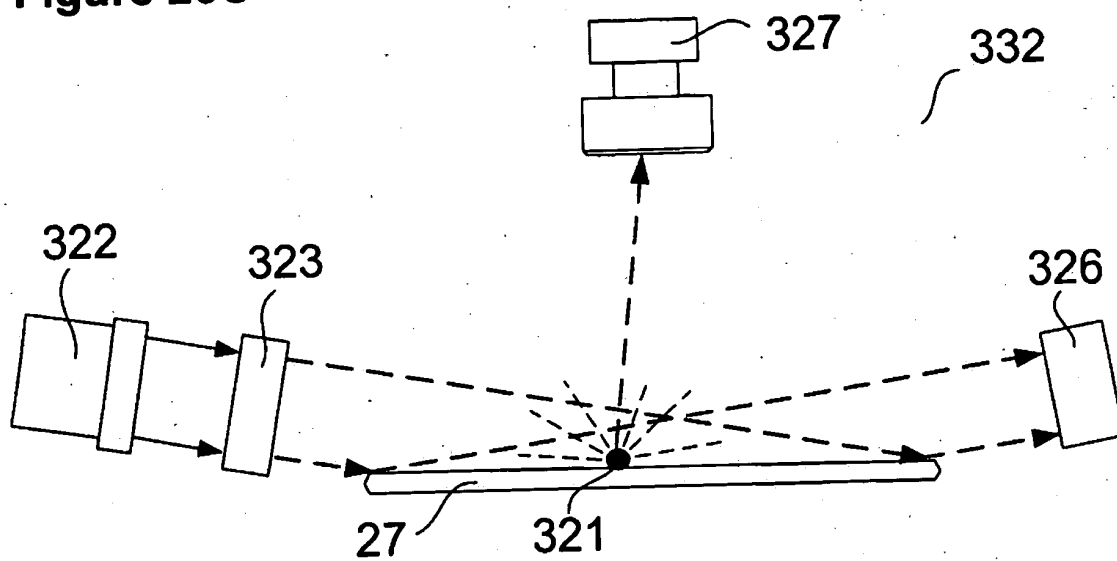


Figure 26D

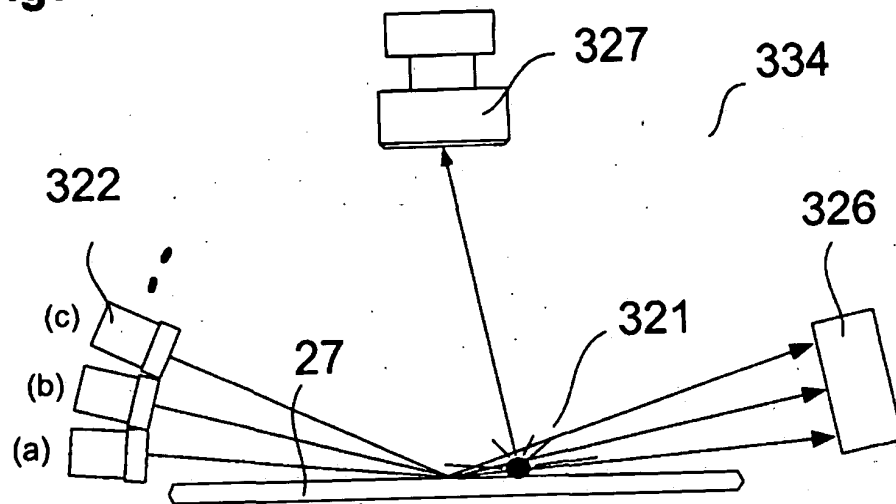


Figure 26E

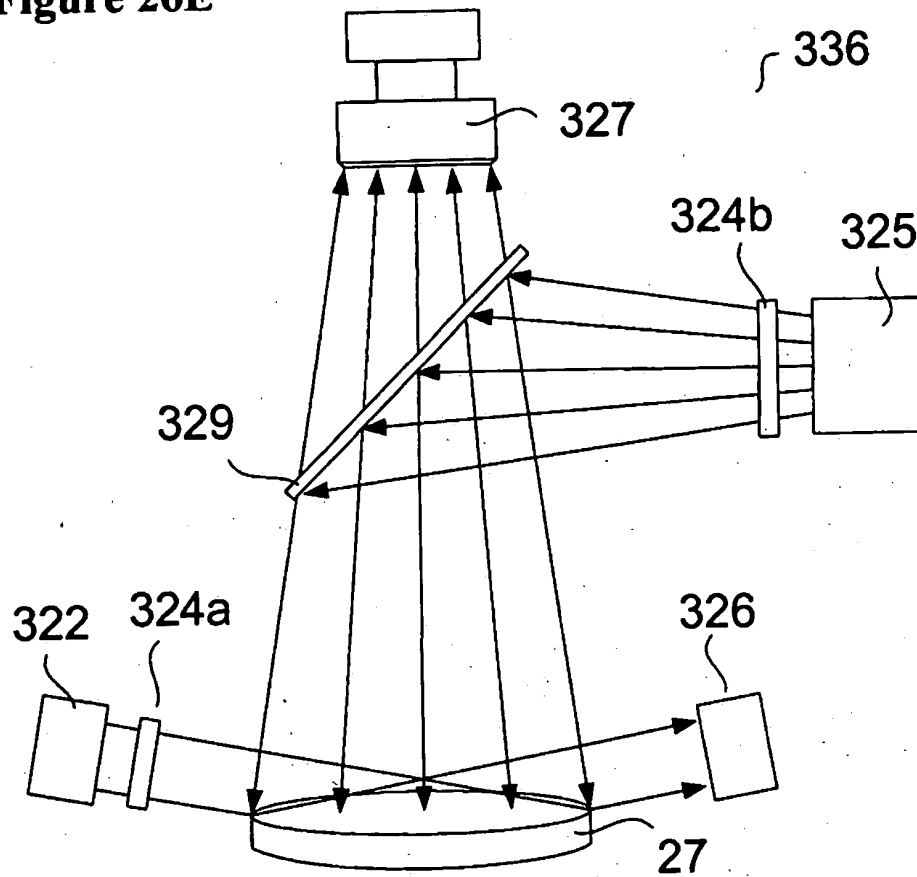


Figure 26F

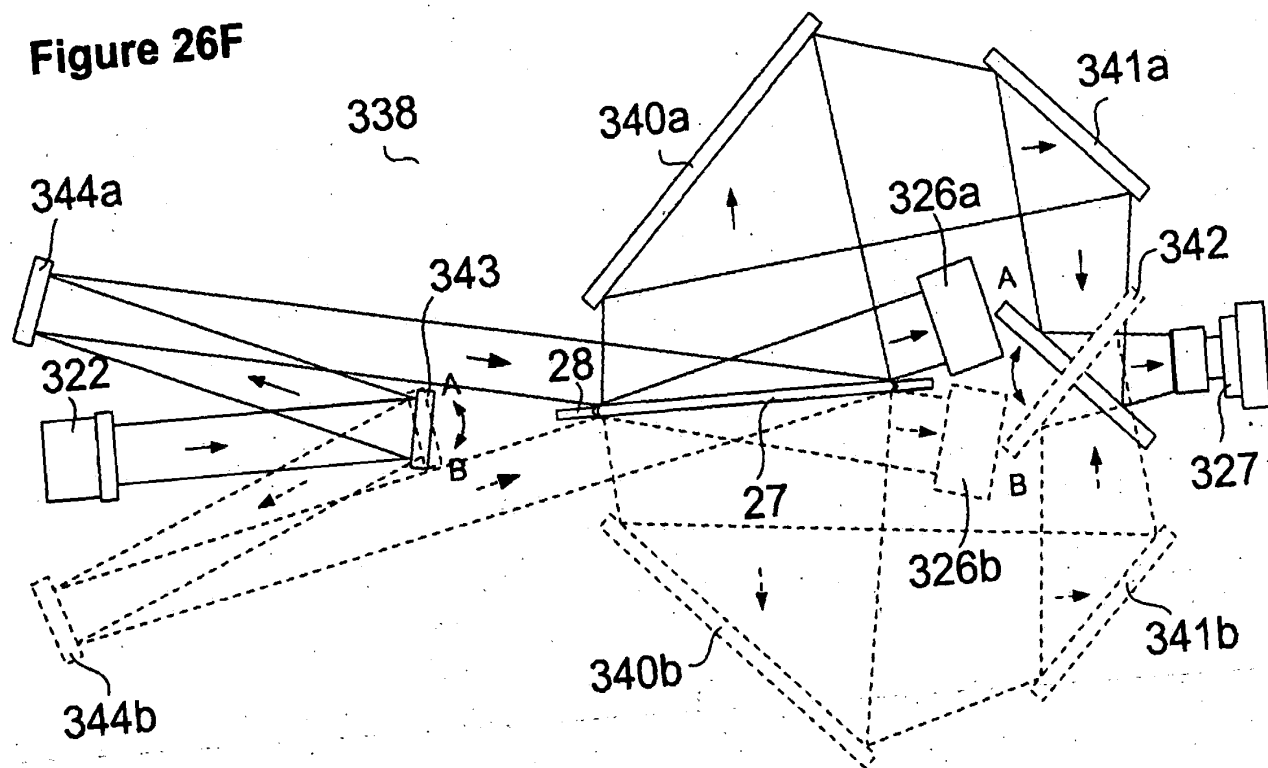


Figure 26G

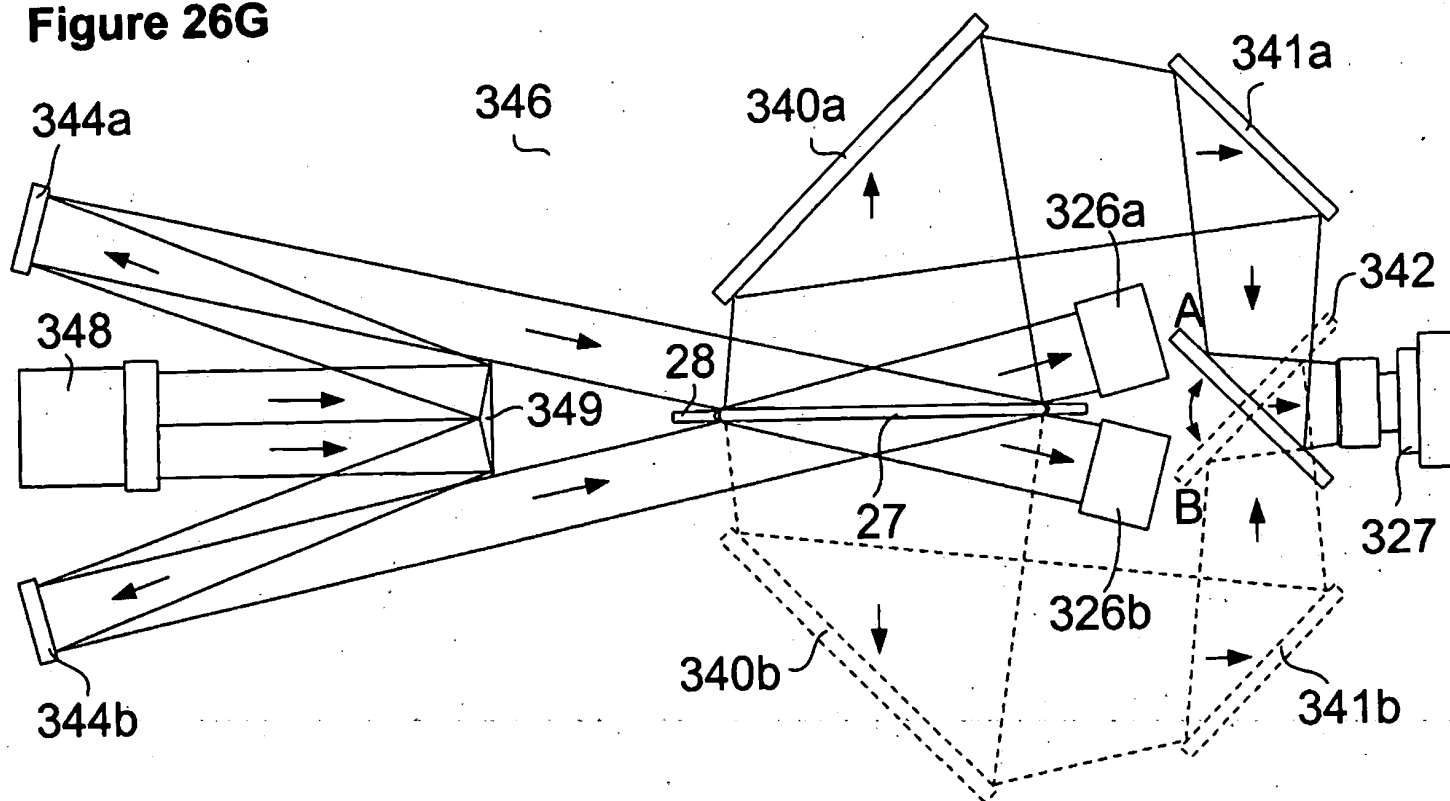


Figure 26H

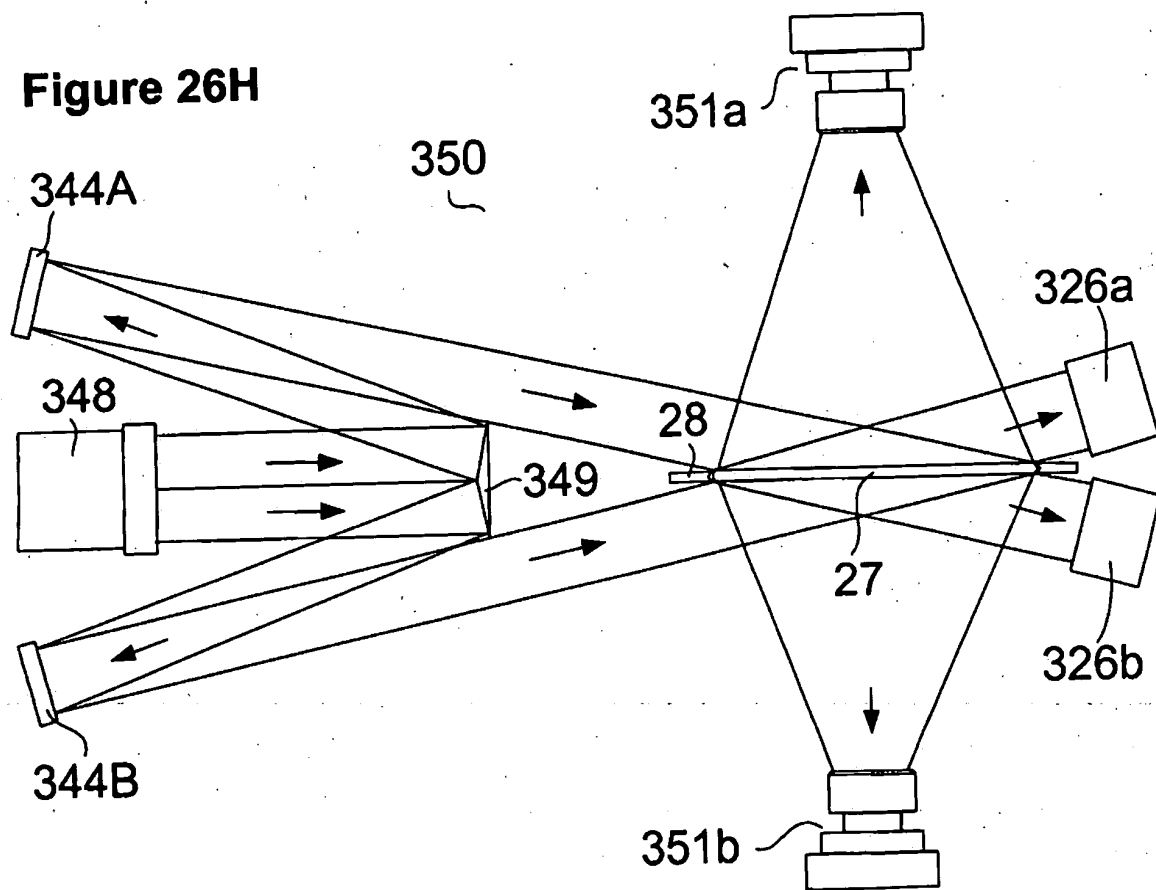


Figure 27A

Figure 27A is a schematic diagram of a robotic arm assembly. The assembly includes a base (25) connected to a control unit (29). A vertical axis (380) passes through the center of a circular platform (382). A horizontal arm (374) is attached to the platform, with a handle (376) and a grip (378). The arm is supported by a series of concentric rings (362) and is connected to a base (364) via a joint (366). A vertical arrow (368) indicates the direction of movement. A dashed line (384) represents the vertical axis. A horizontal line (370) is also shown.

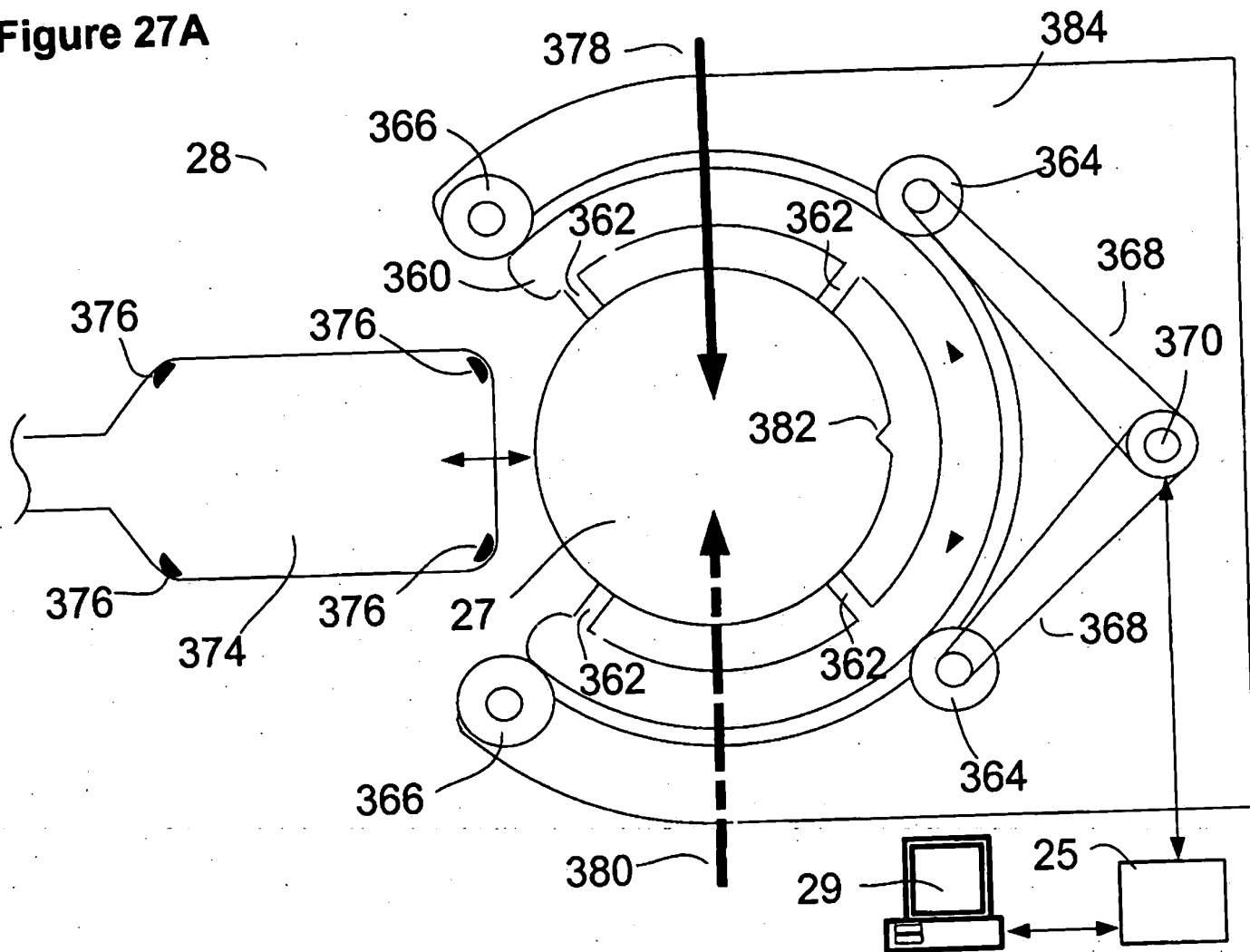


Figure 27B

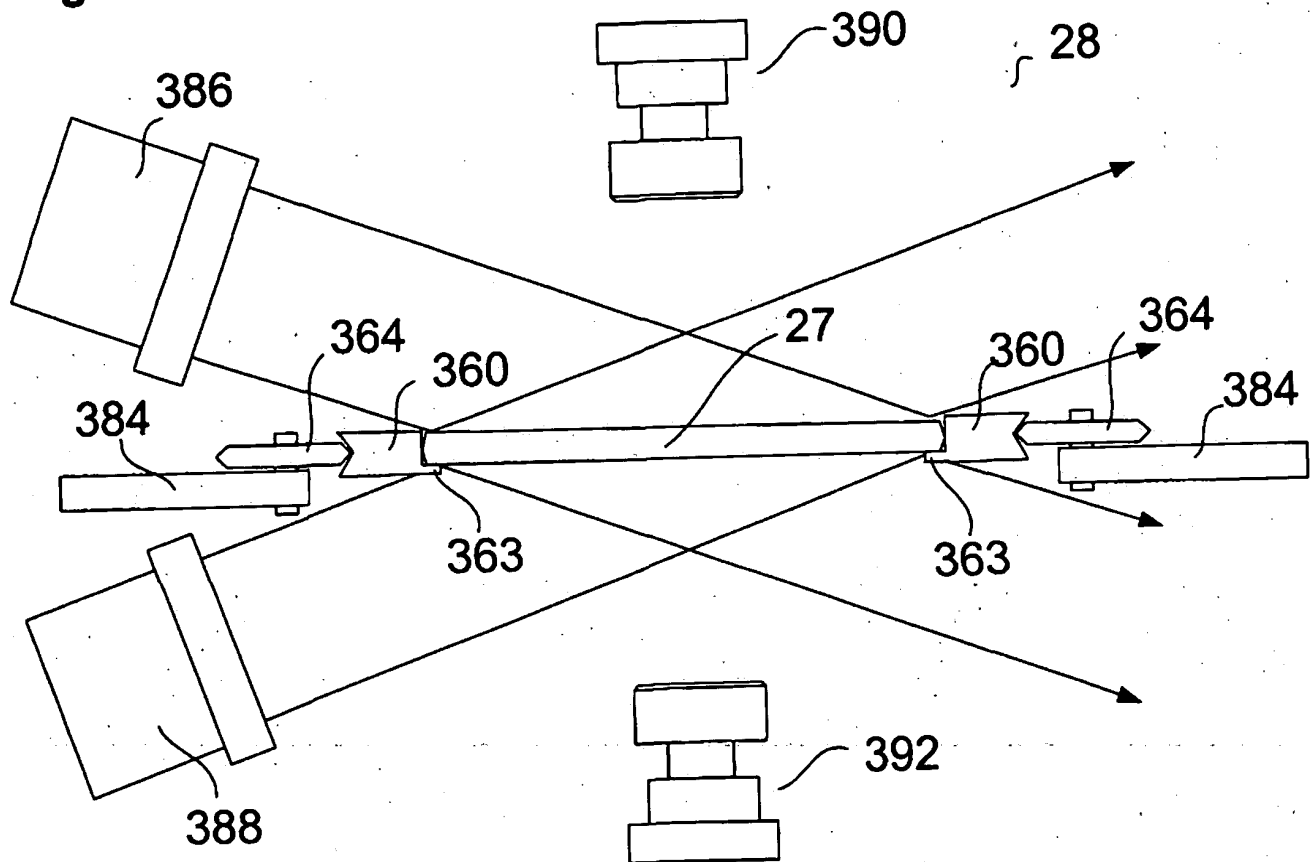


Figure 28A

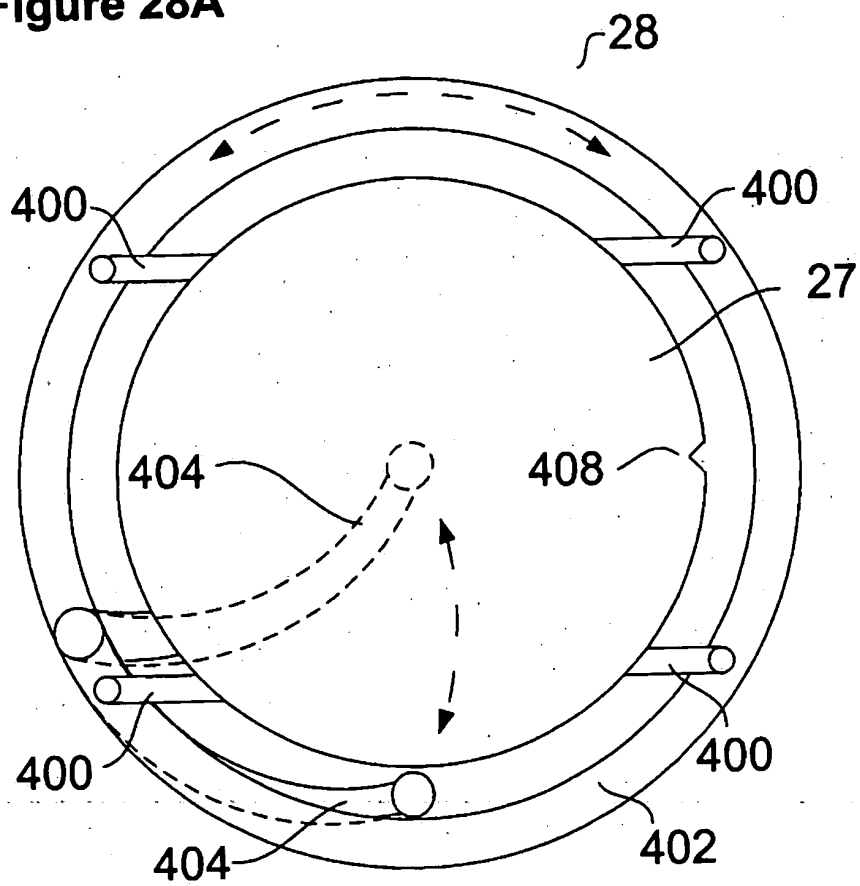


Figure 28B

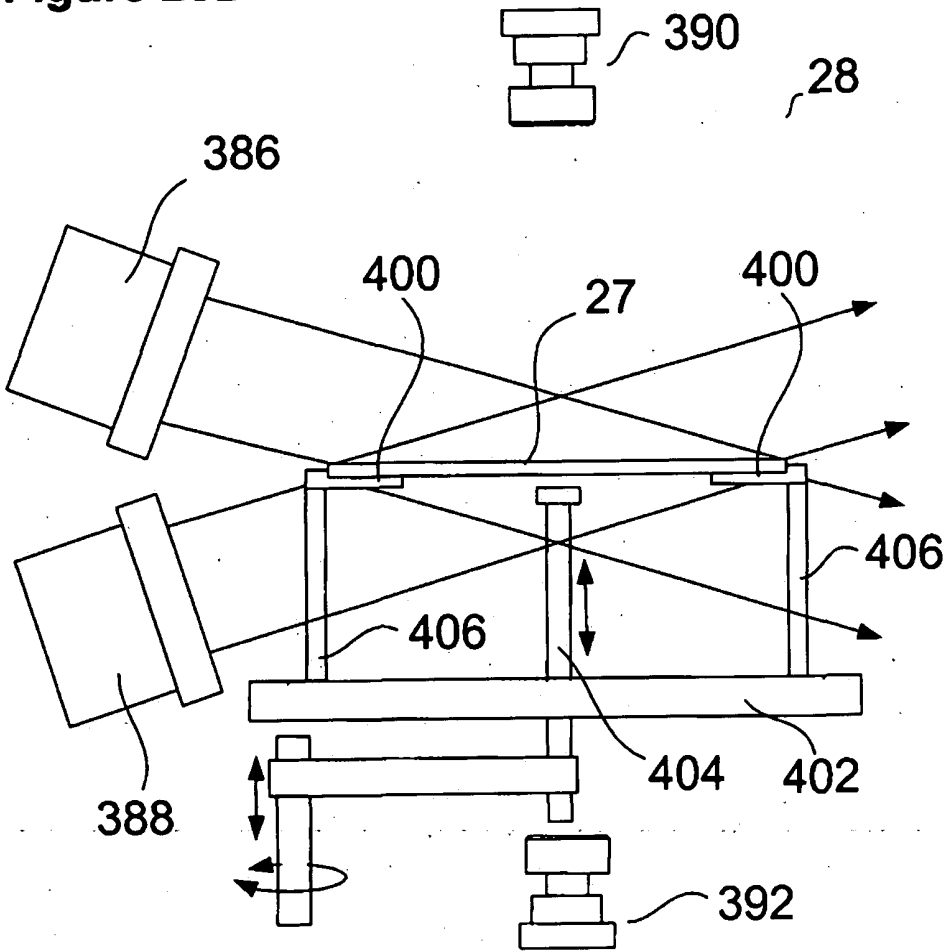


Figure 28C

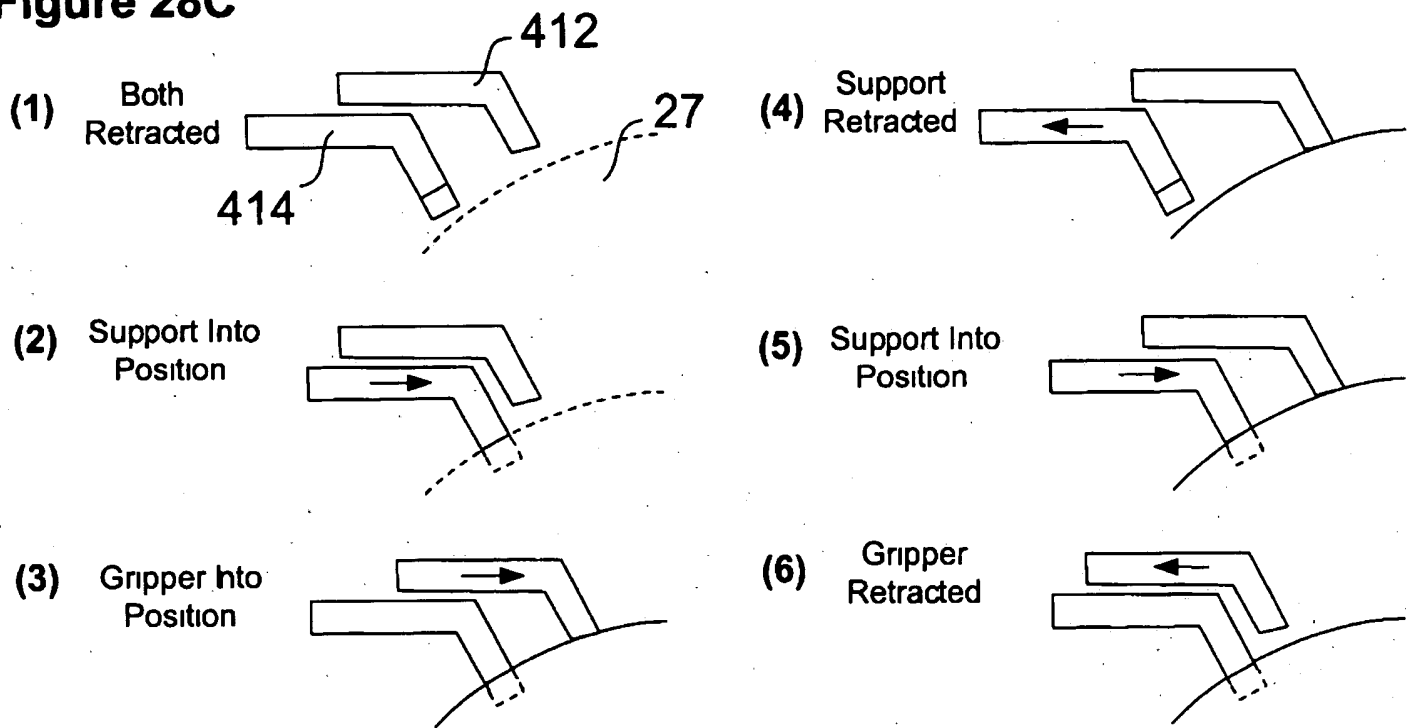


Figure 28D

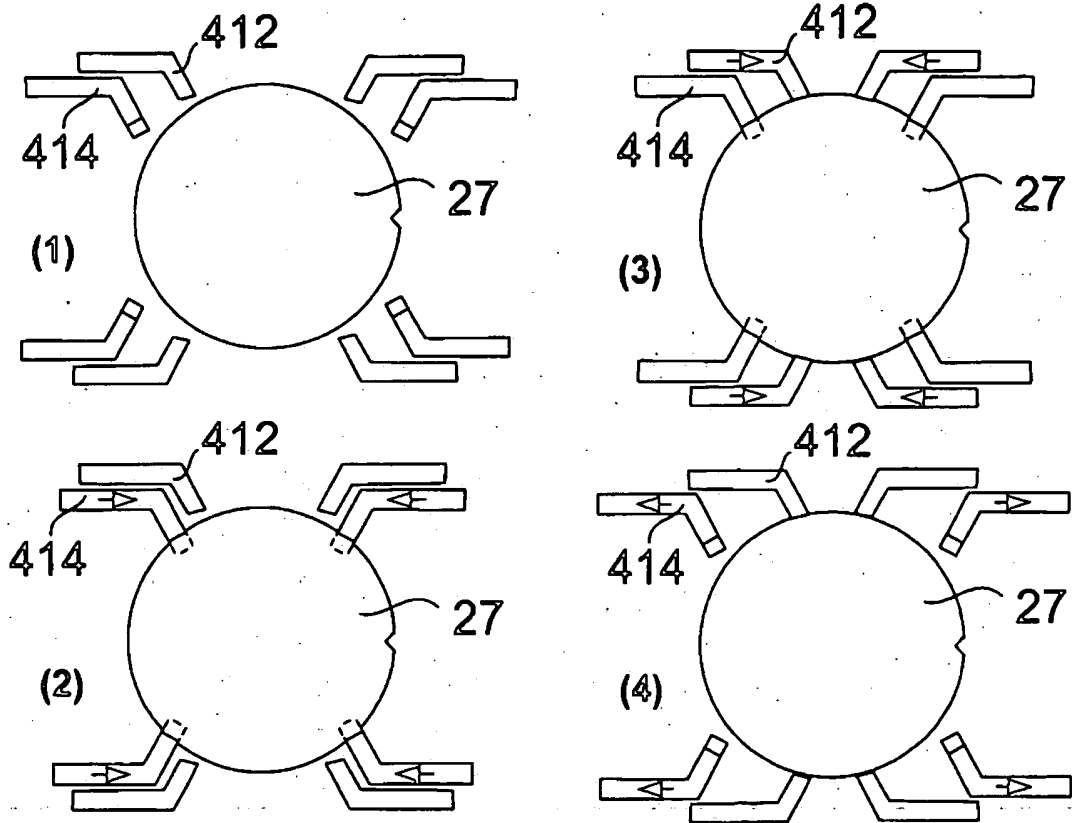


Figure 28E

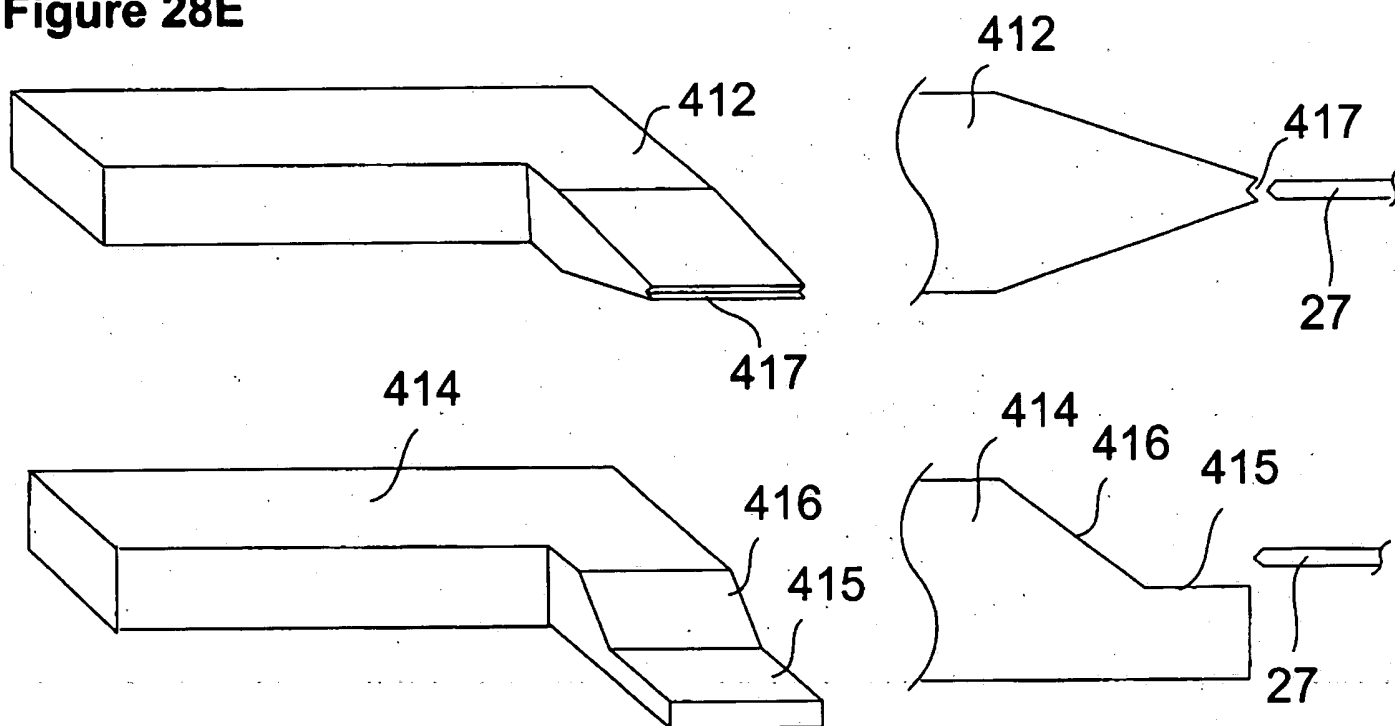


Figure 28F

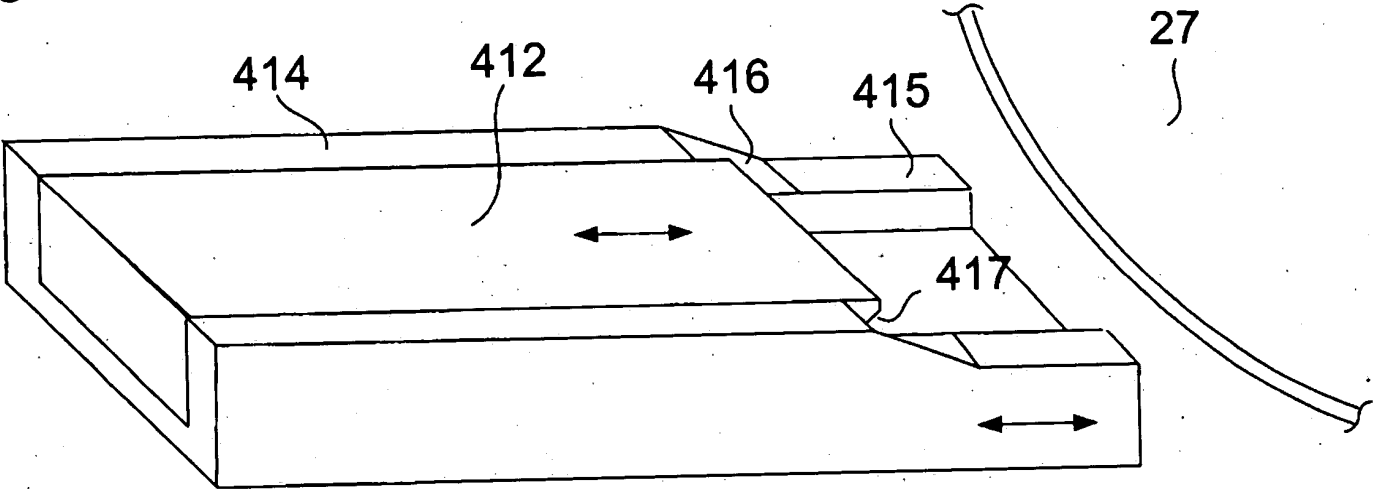


Figure 29

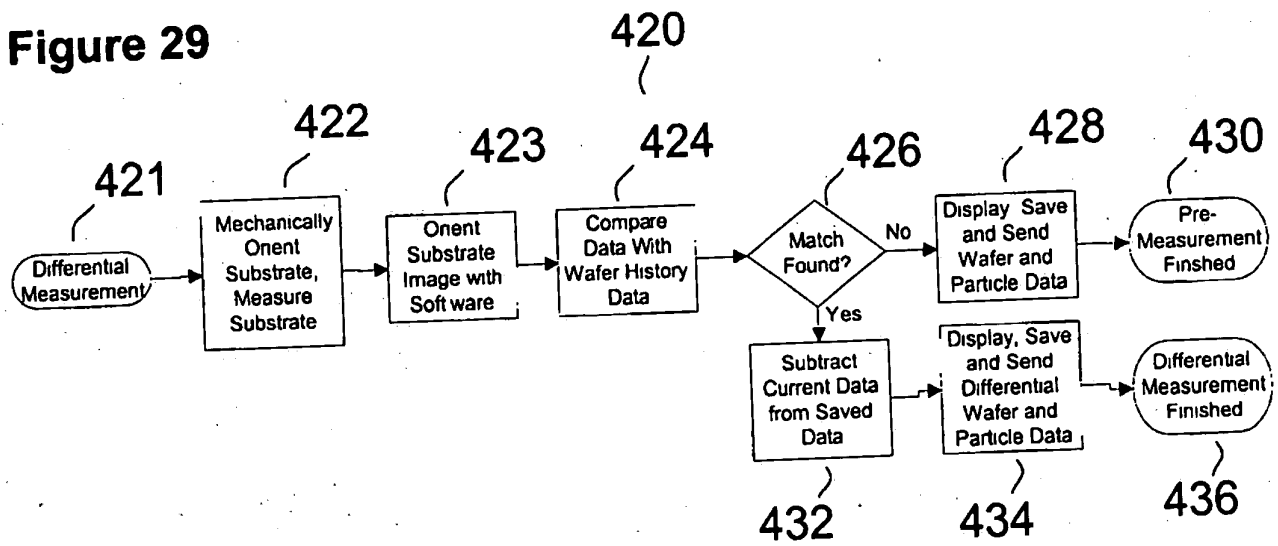


Figure 30

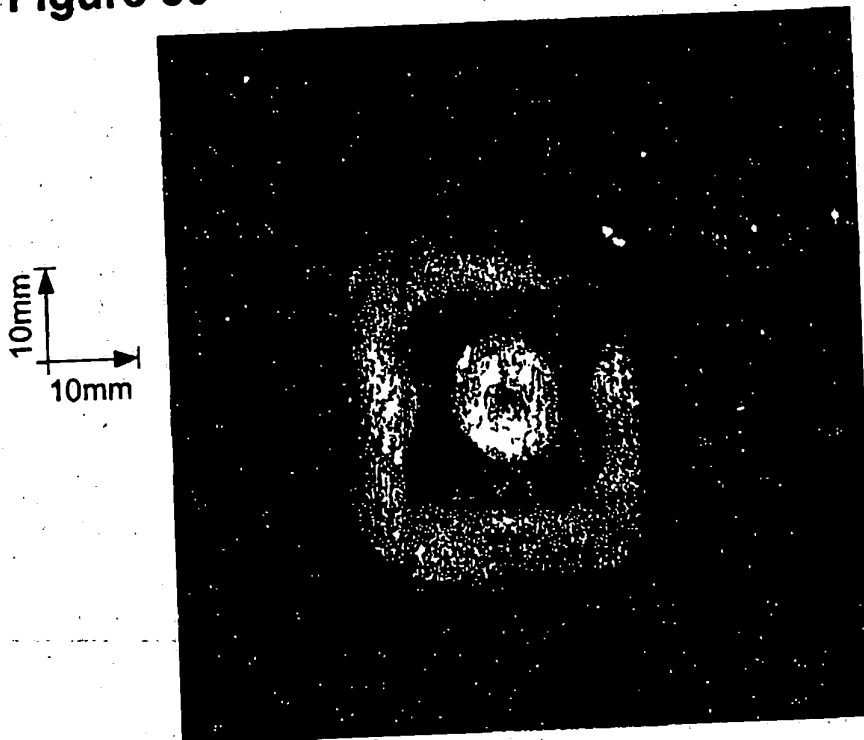


Figure 31

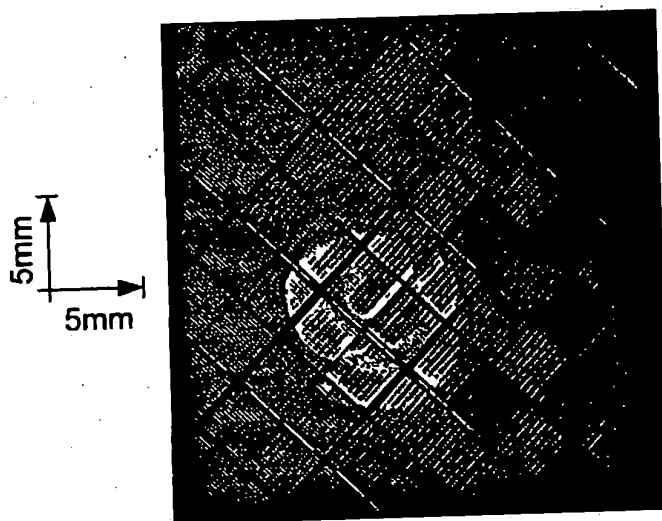


Figure 32

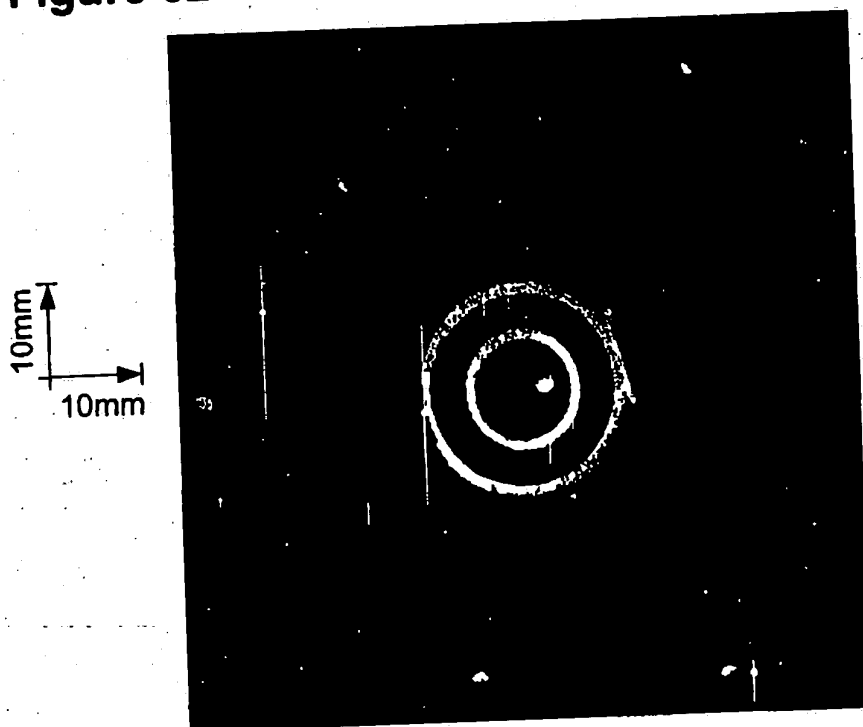


Figure 33

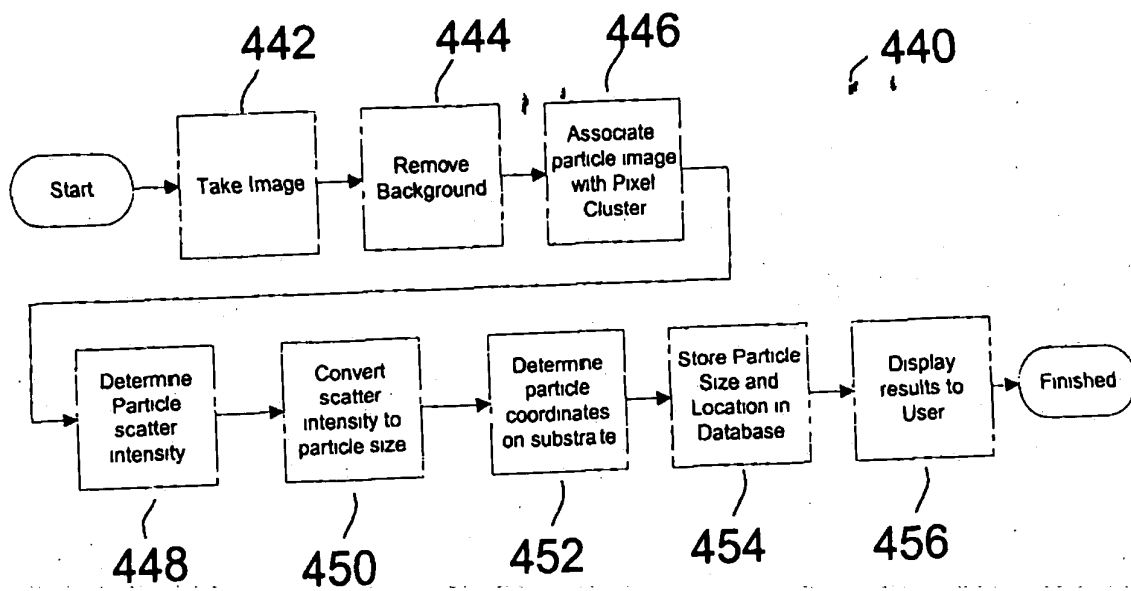


Figure 34

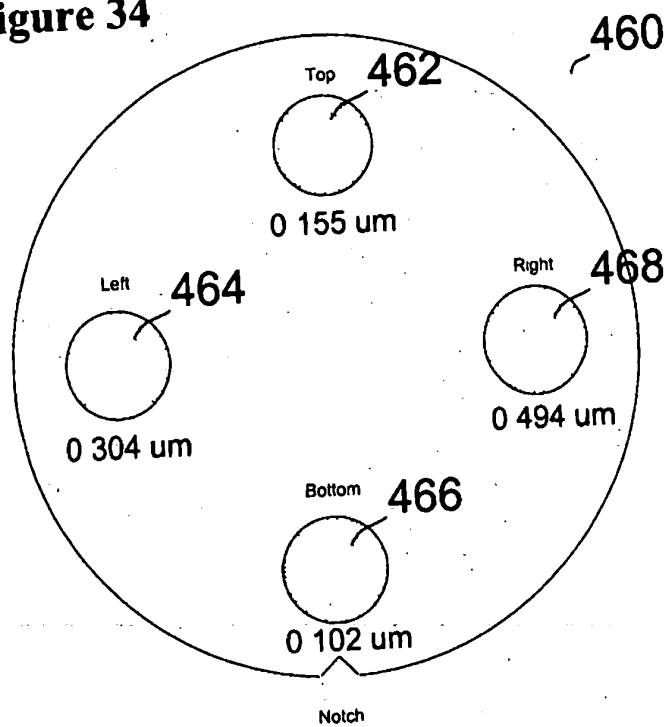


Figure 35

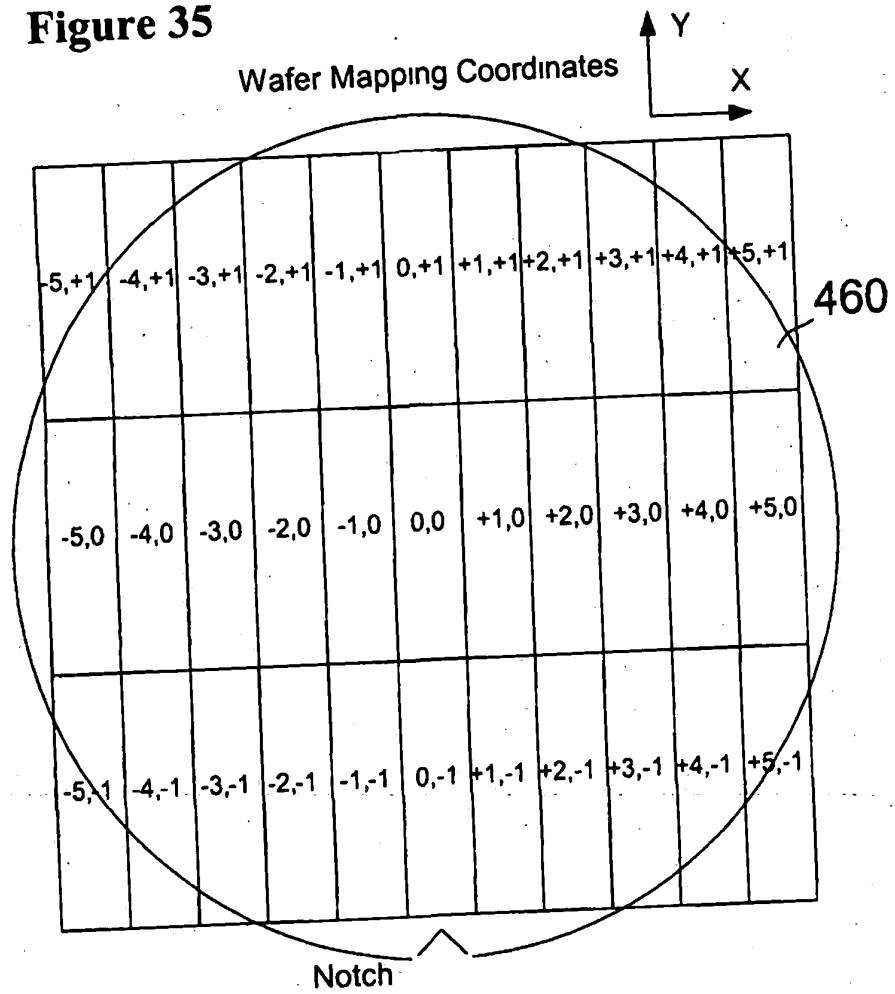


Figure 36



Figure 37

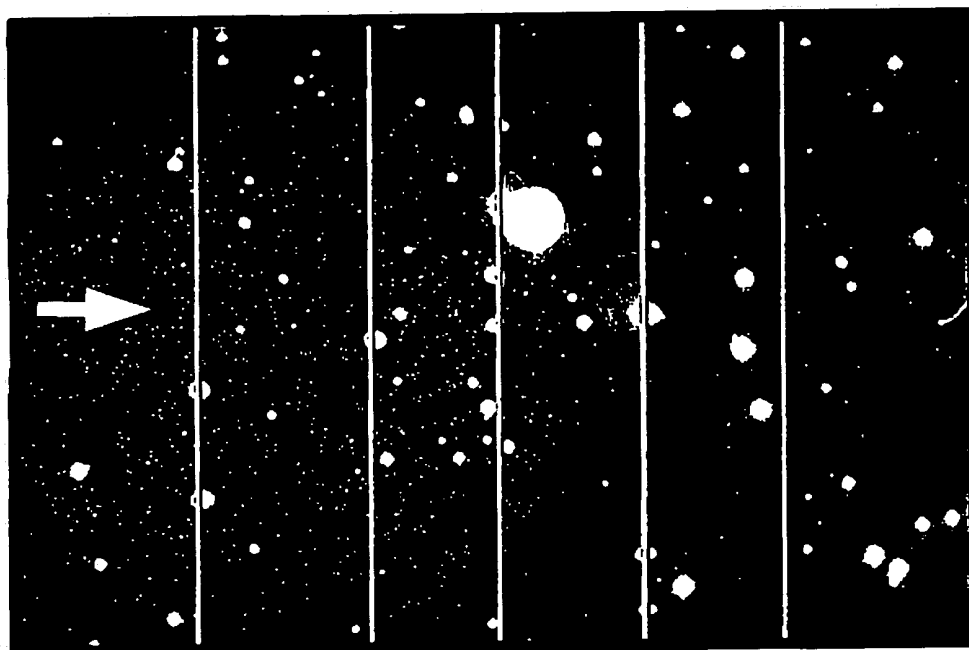


Figure 38

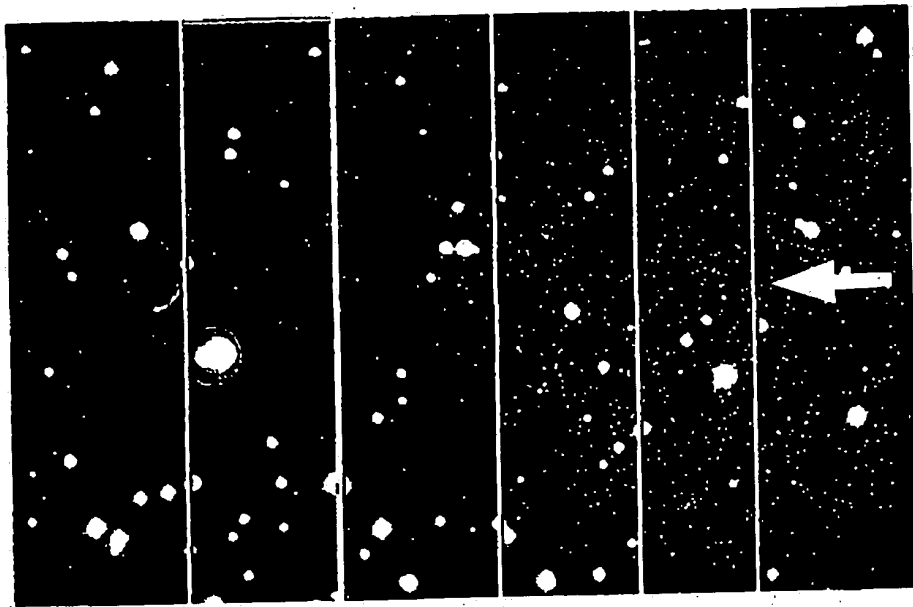


Figure 39

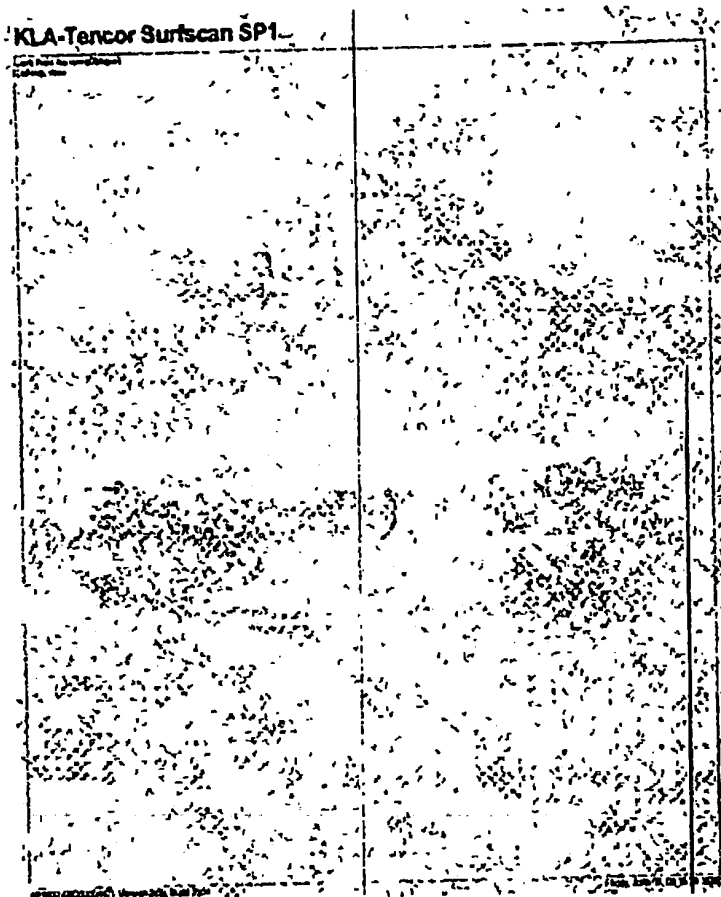


Figure 40 KLA-Tencor Surtscan SP1



KLA-Tencor Surfscan SP1

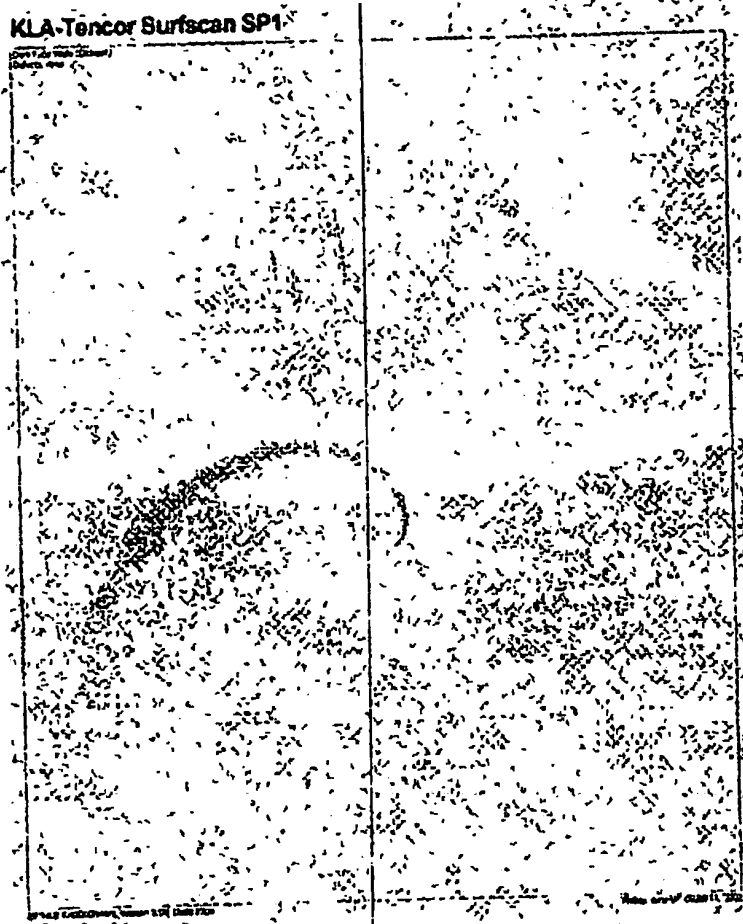


Figure 42

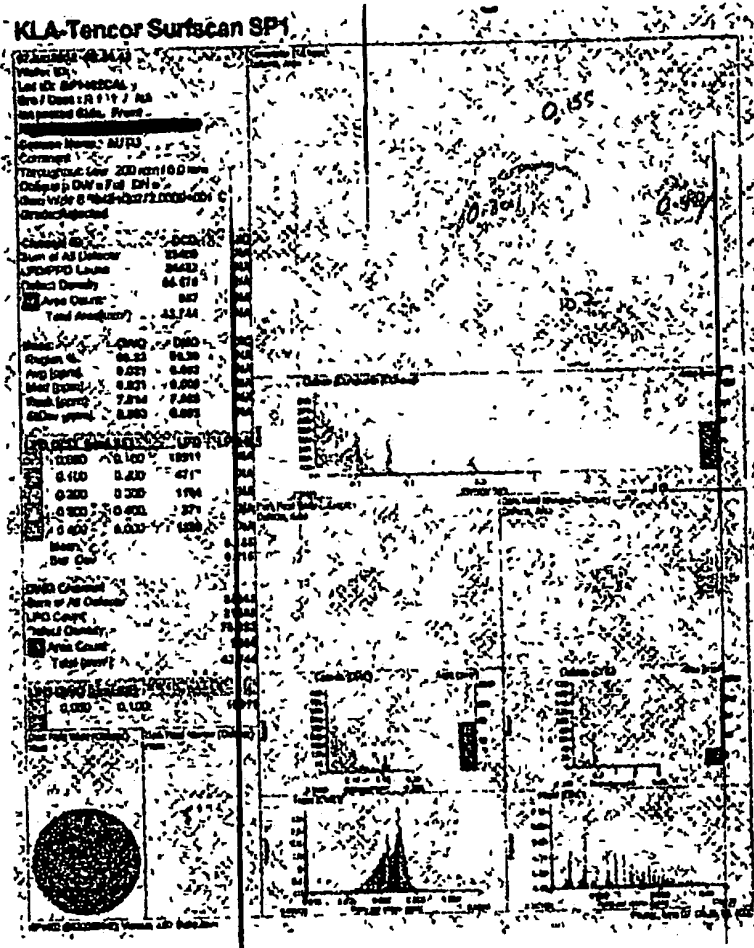


Figure 43

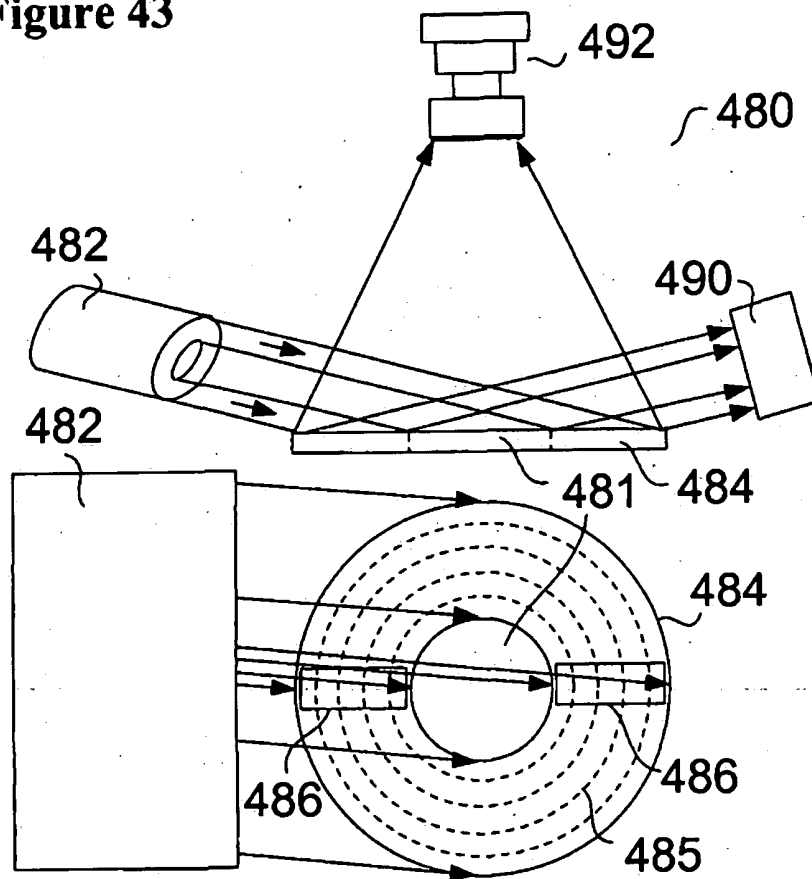


Figure 44

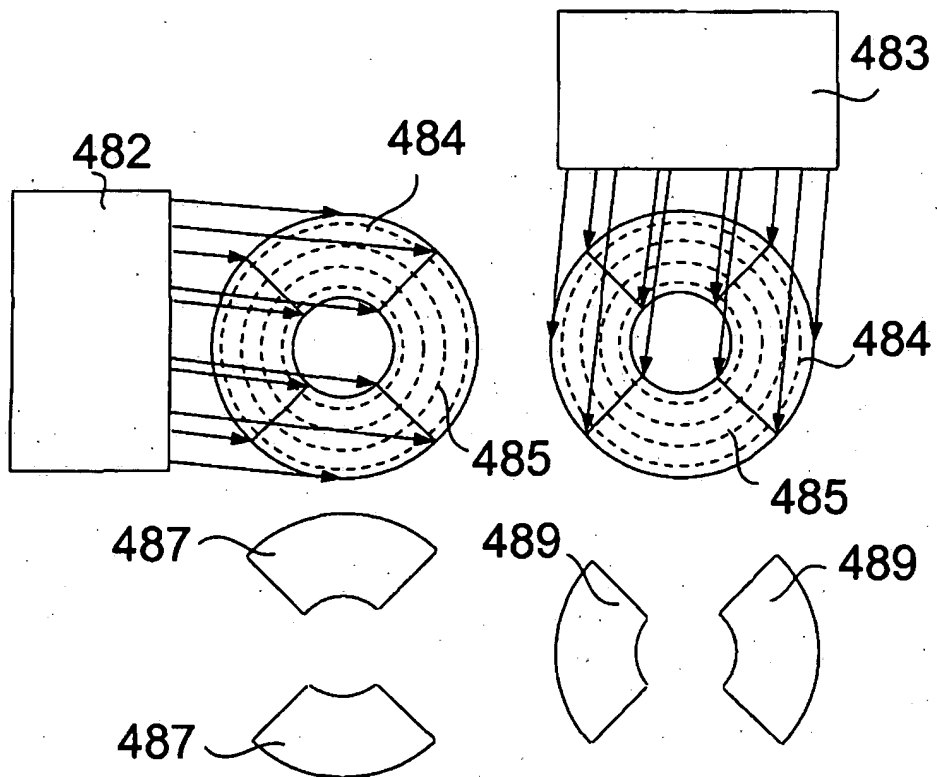


Figure 45

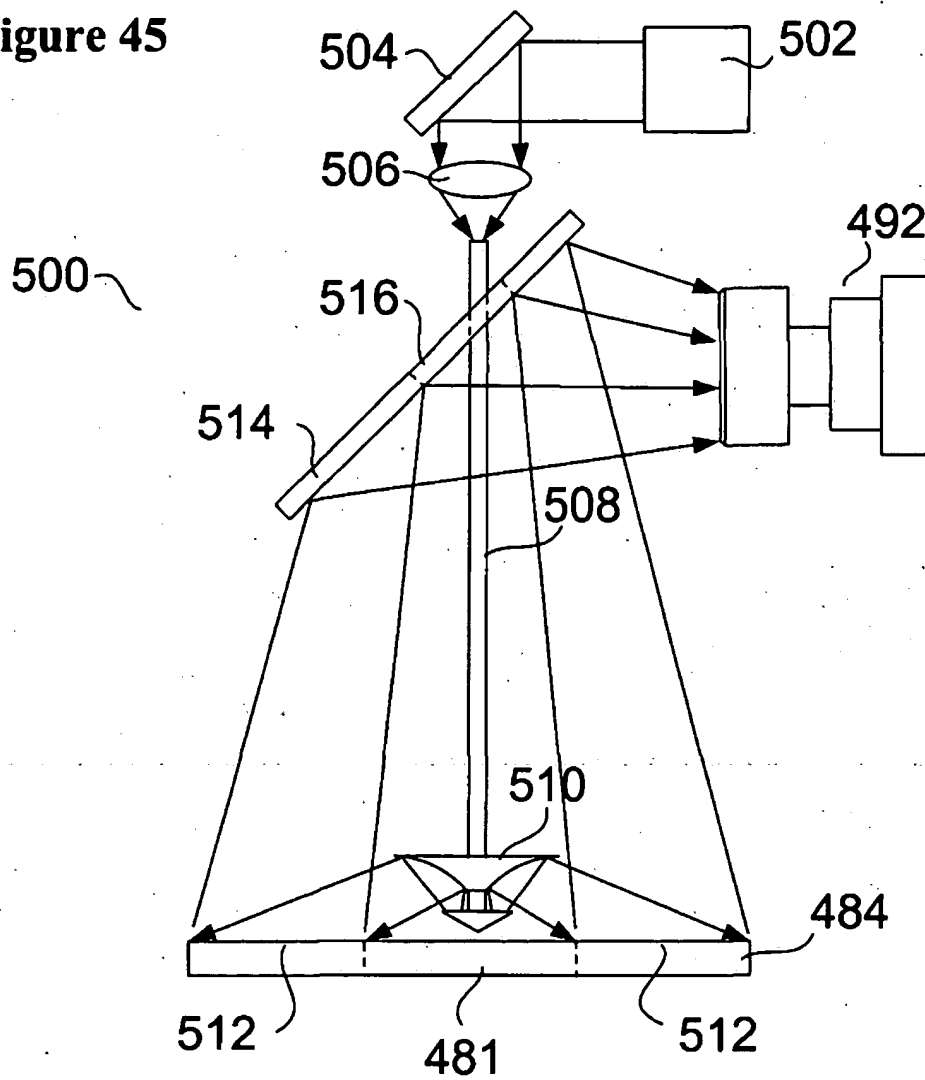


Figure 46

520

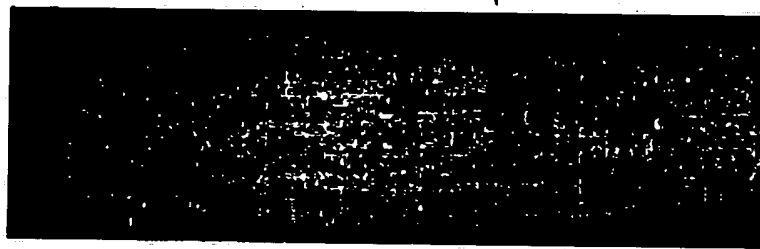
?



1 mm

522

?



1 mm

Figure 47

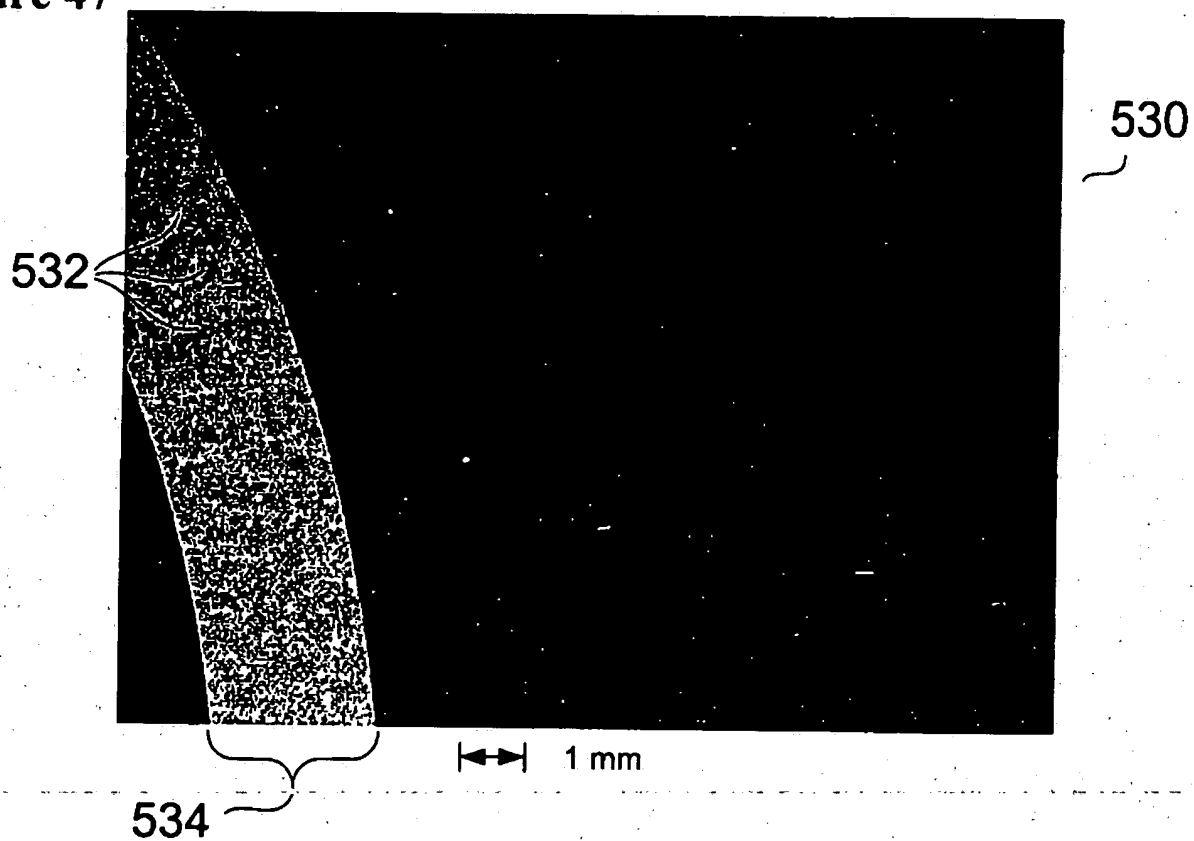


Figure 48

